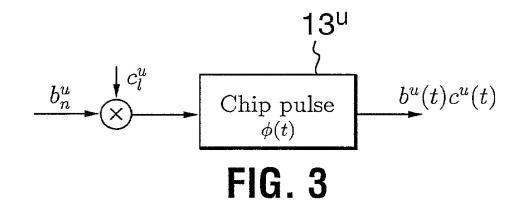
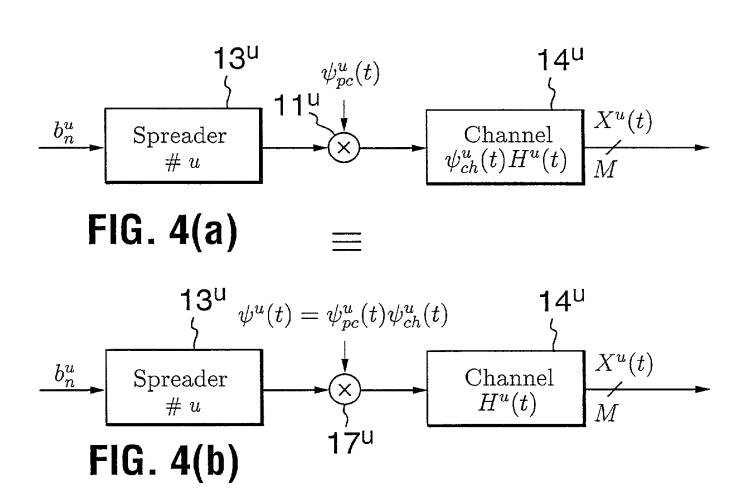
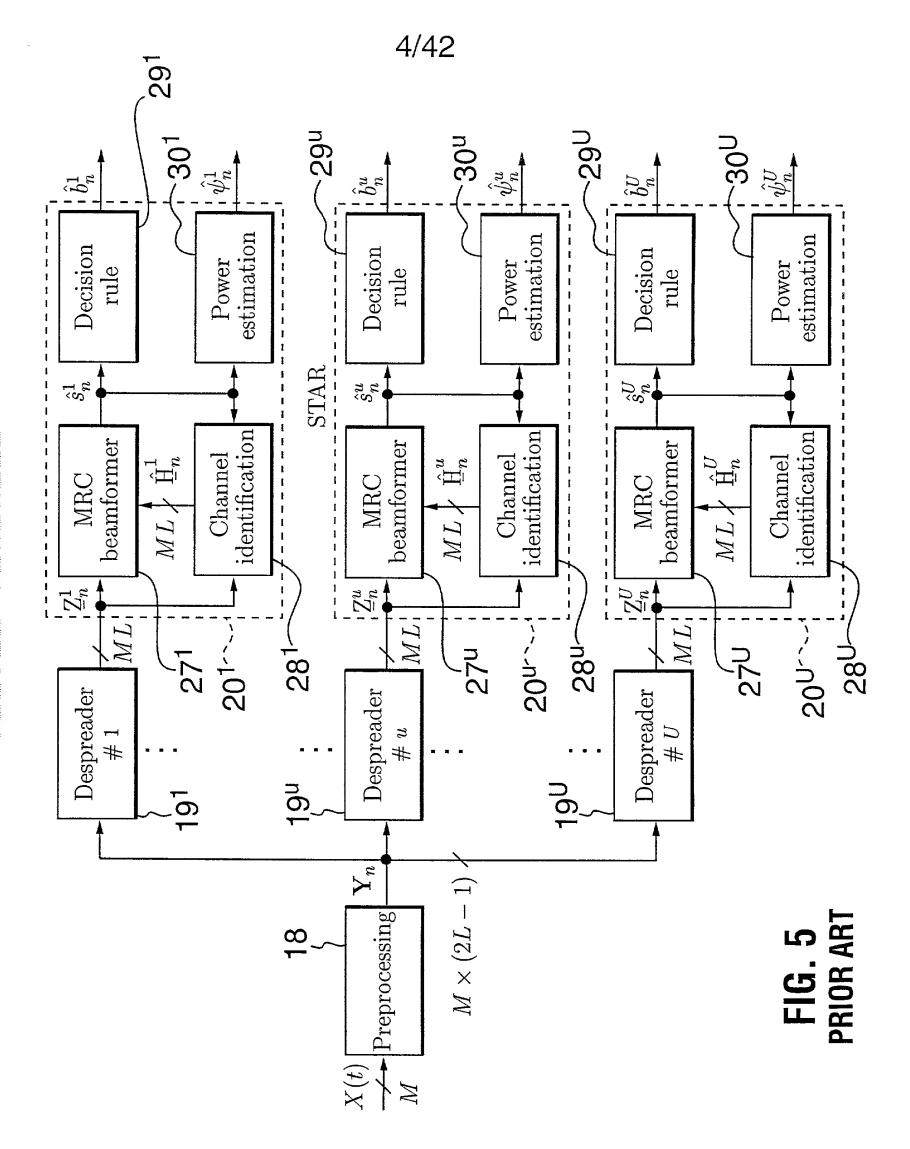


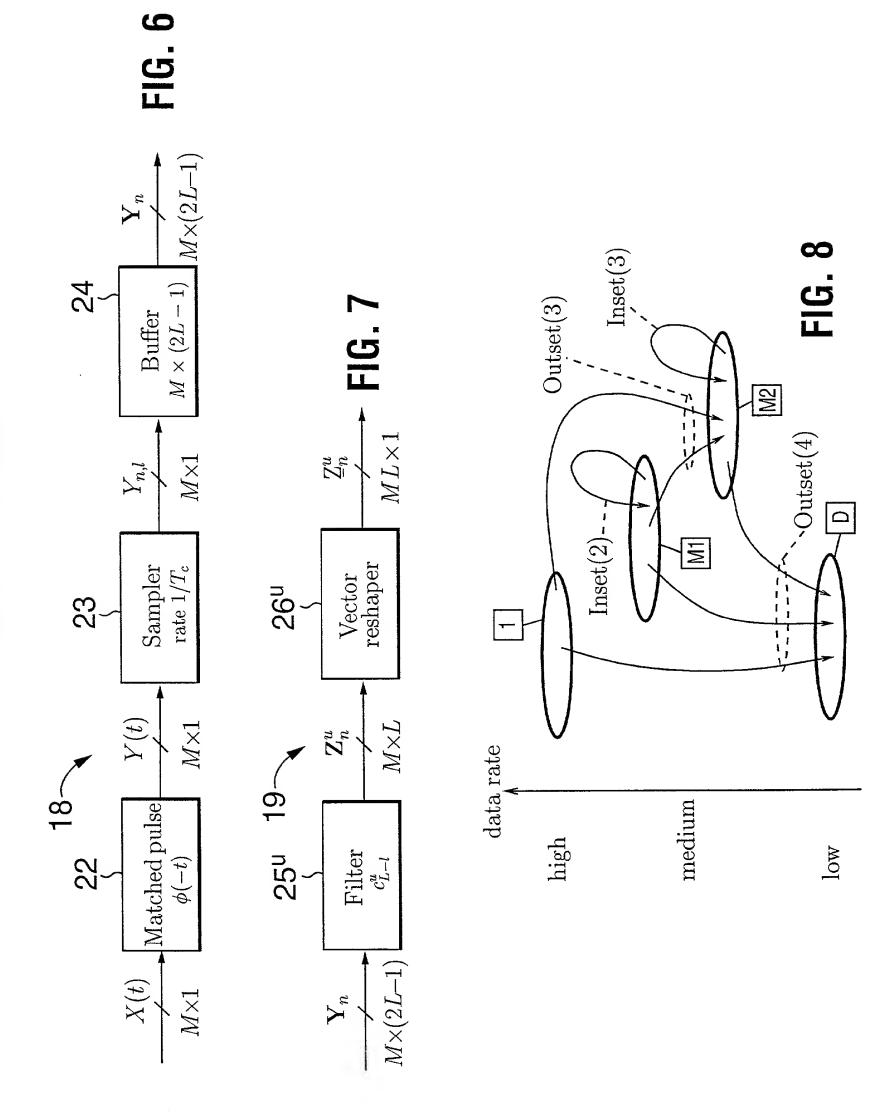
FIG. 2

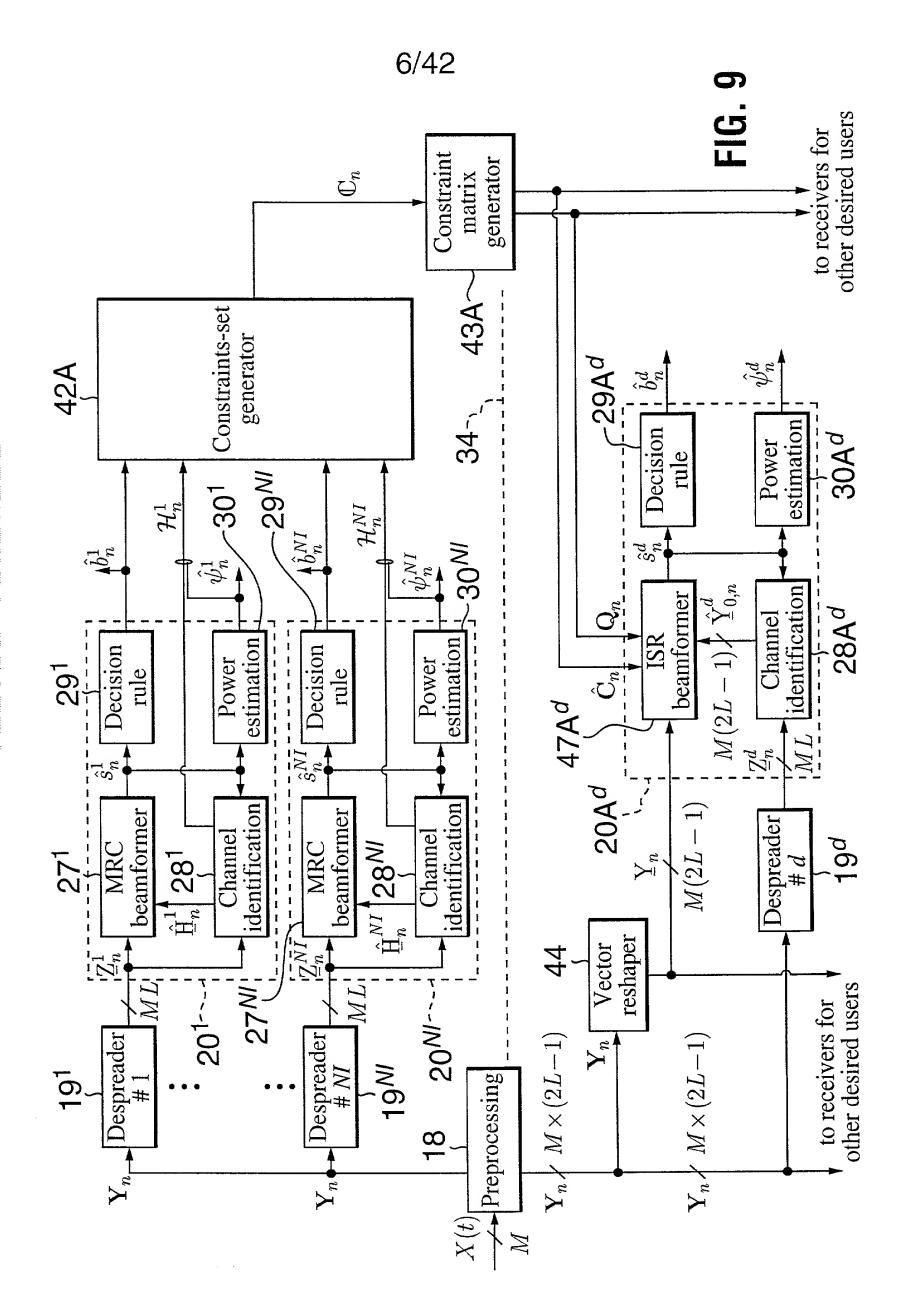


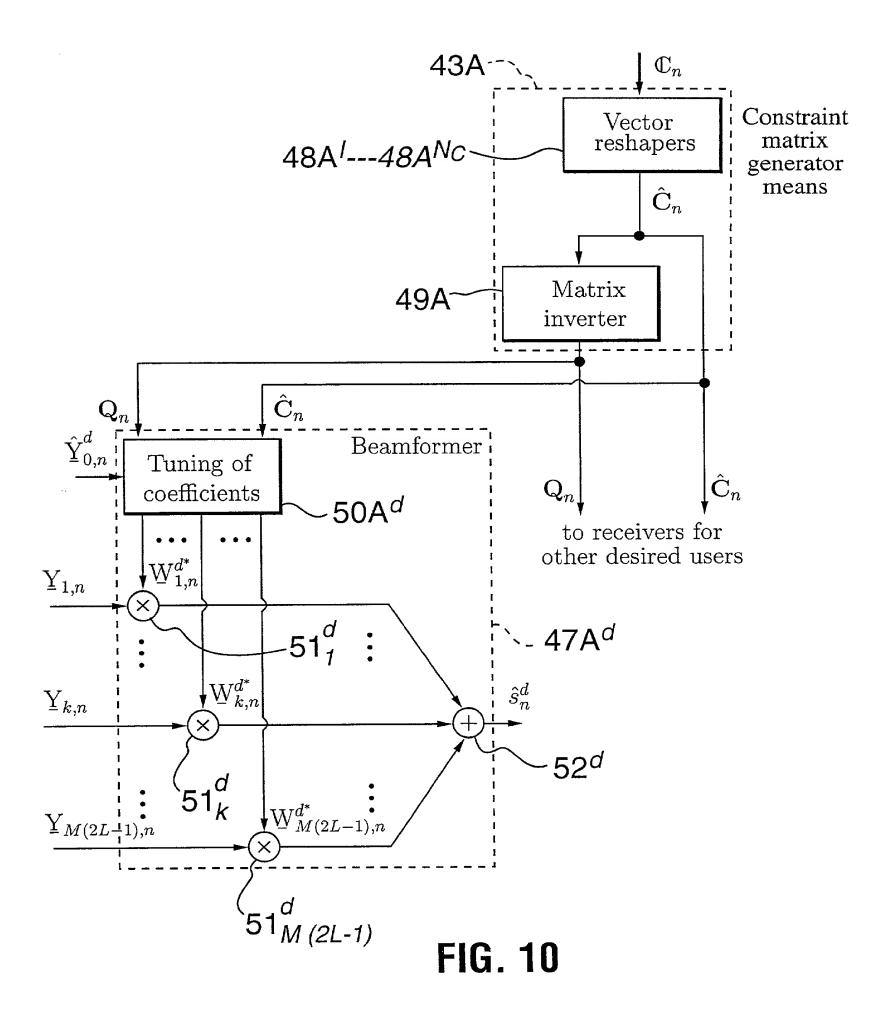


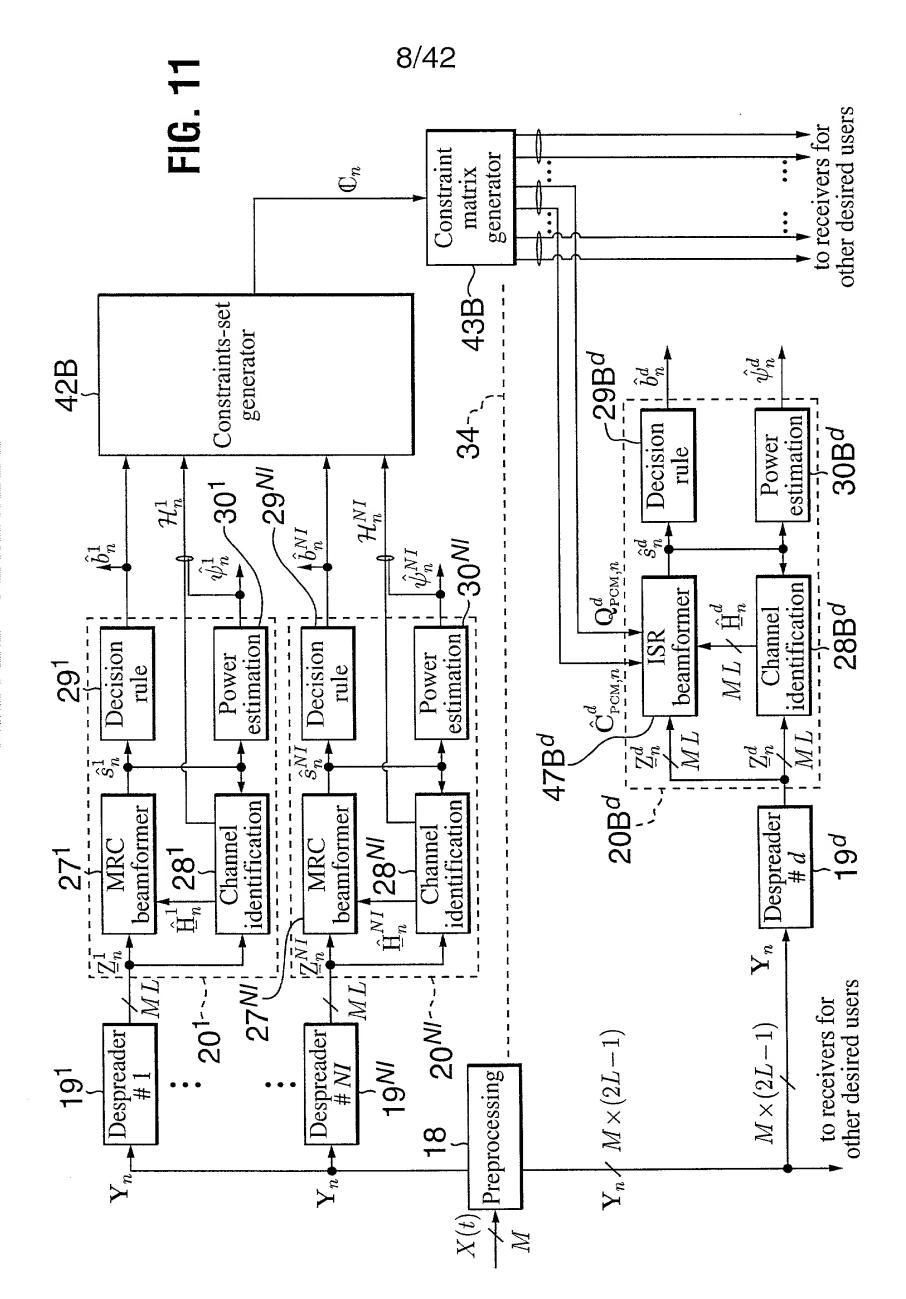












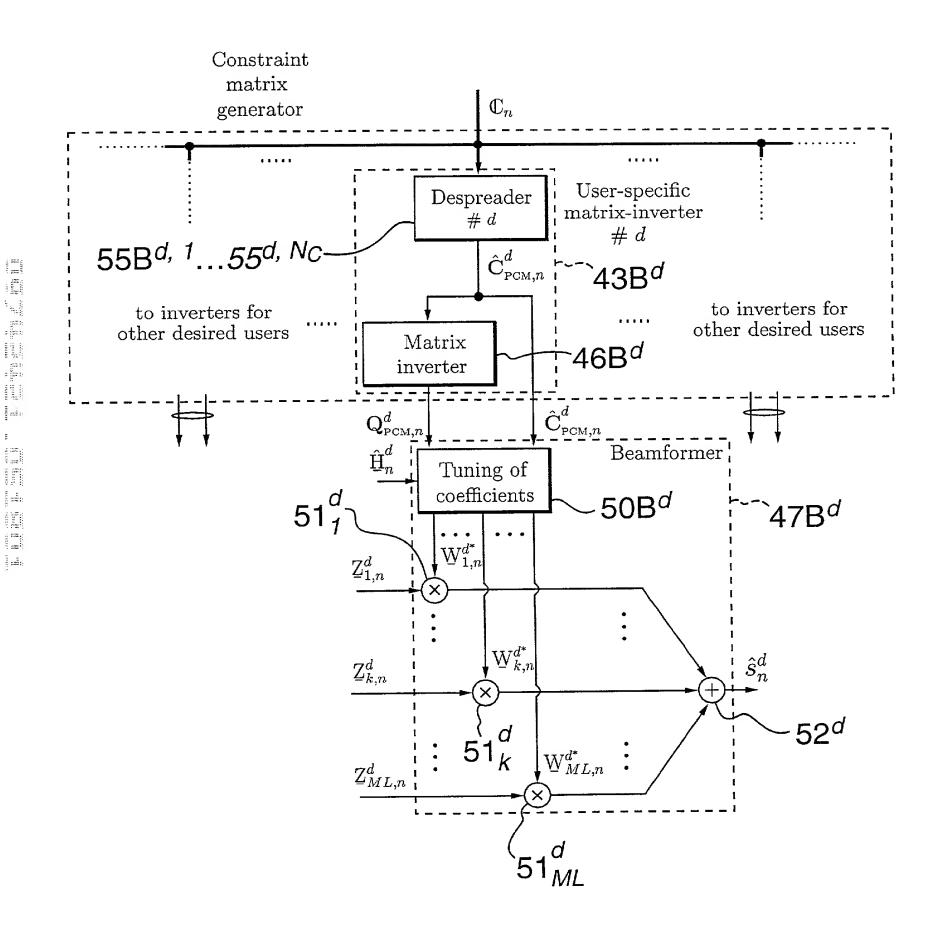
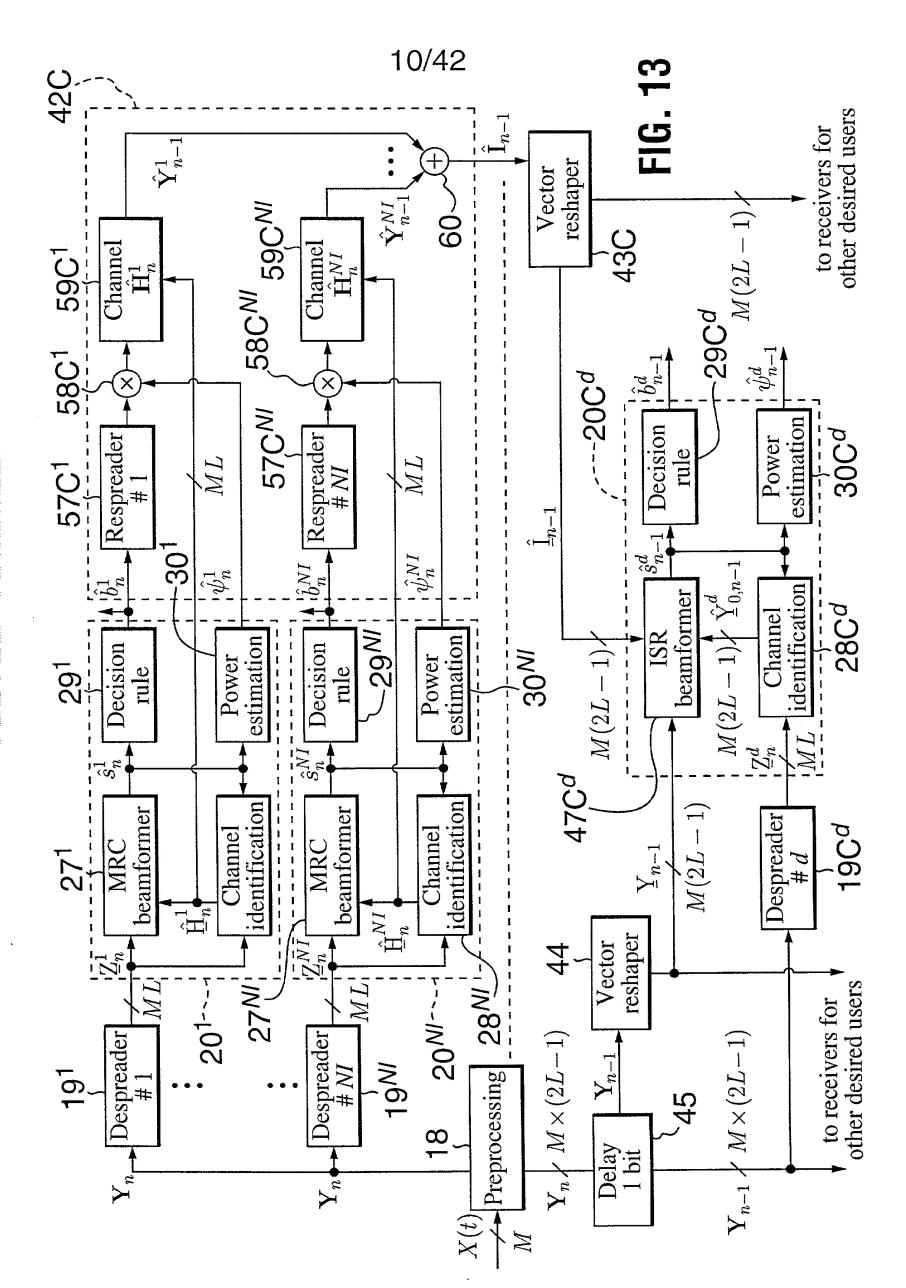
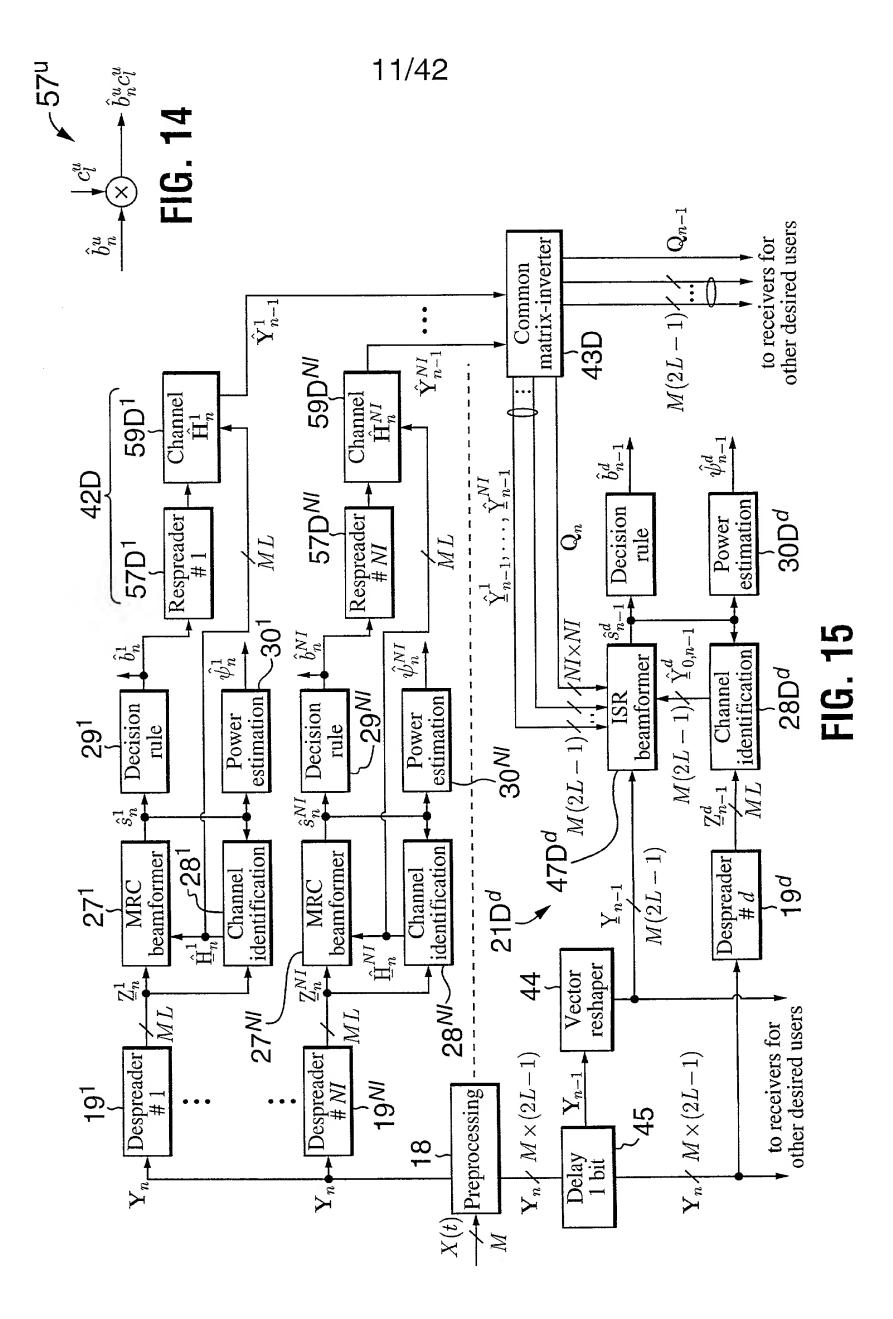
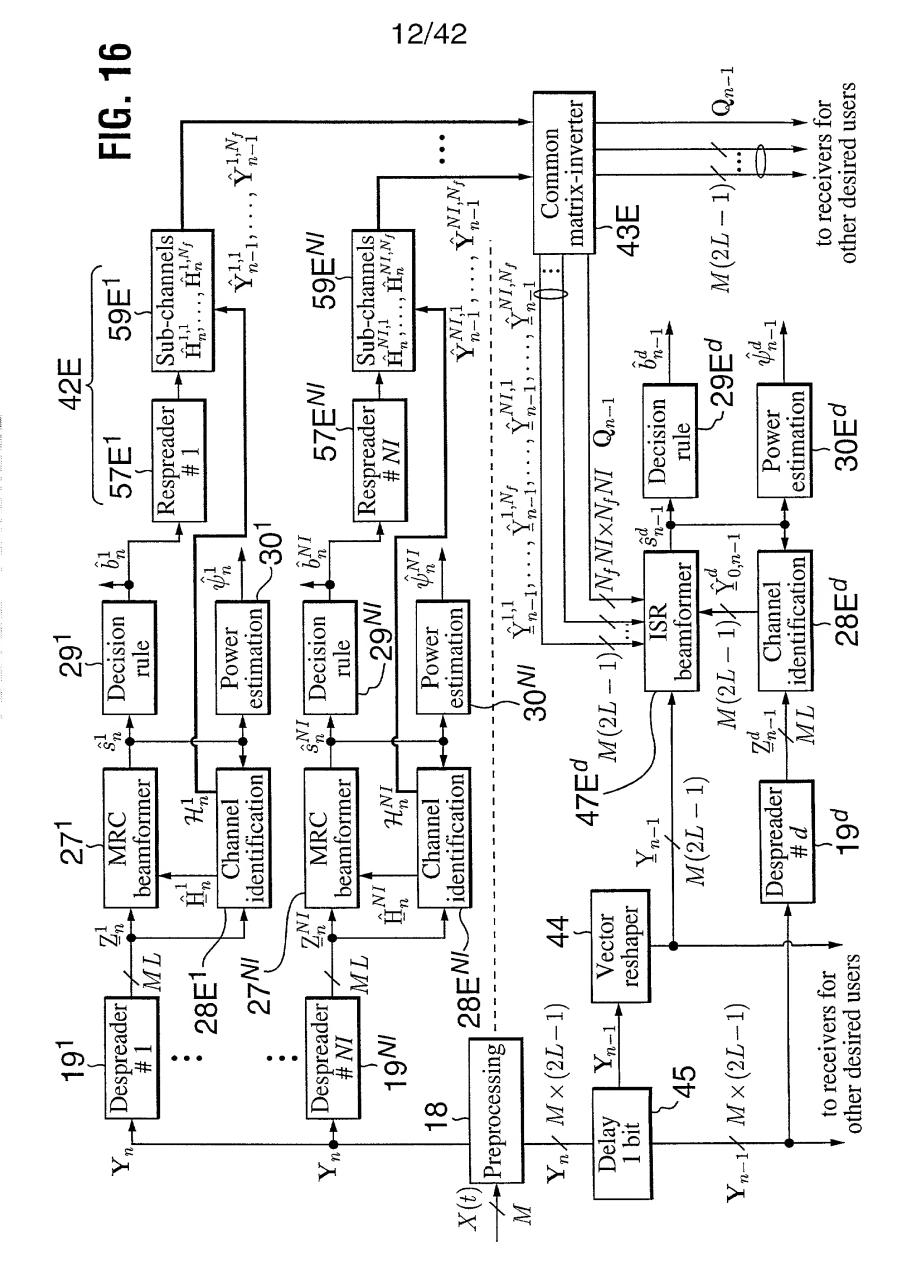
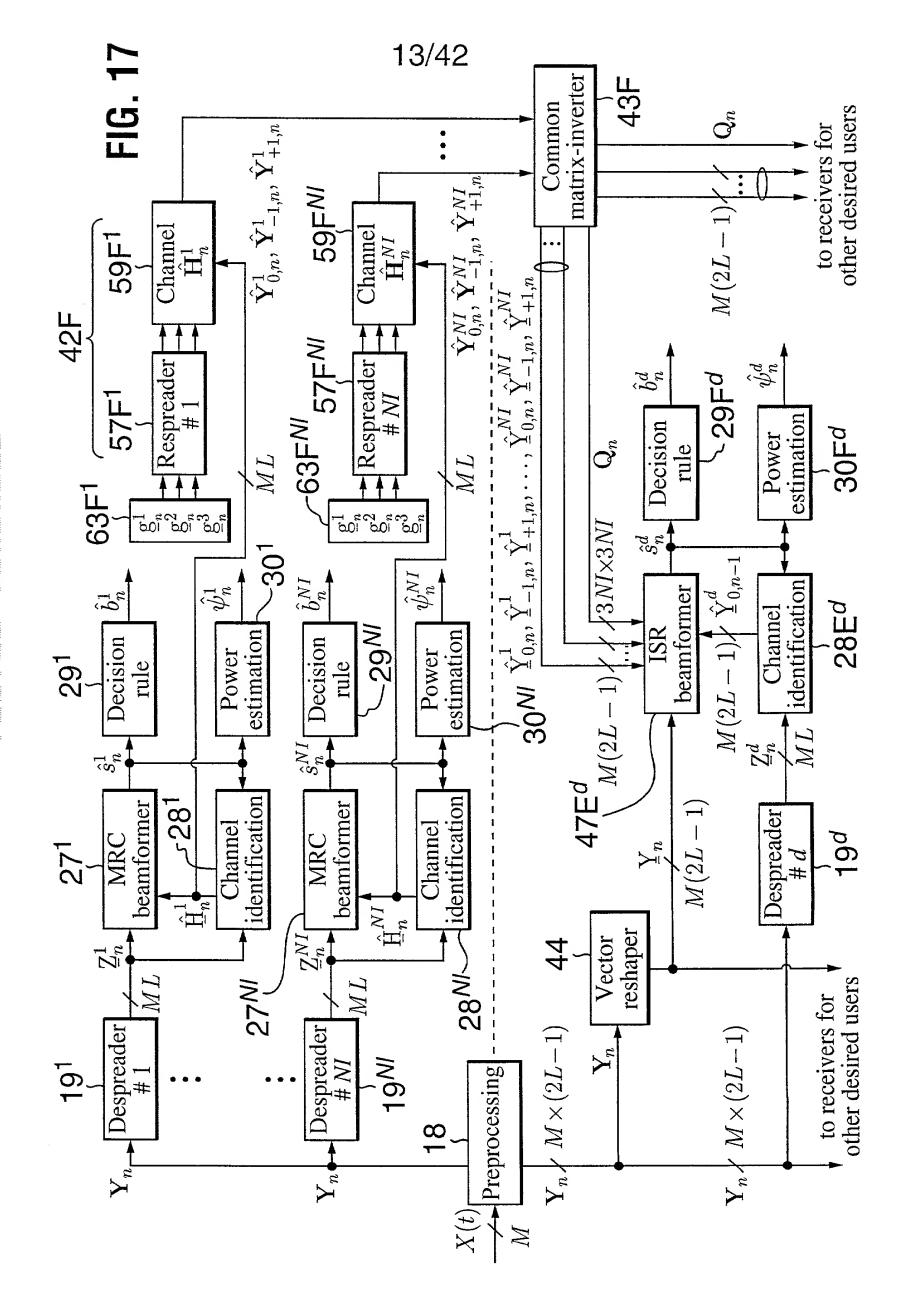


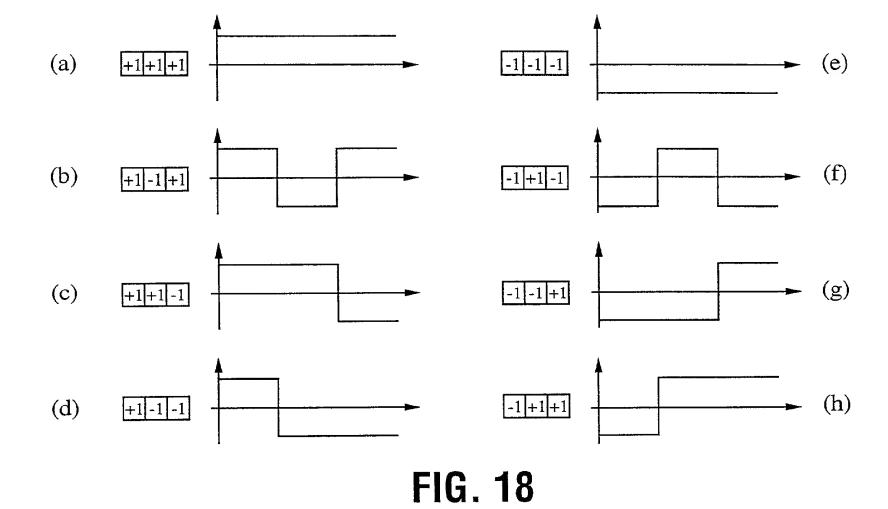
FIG. 12



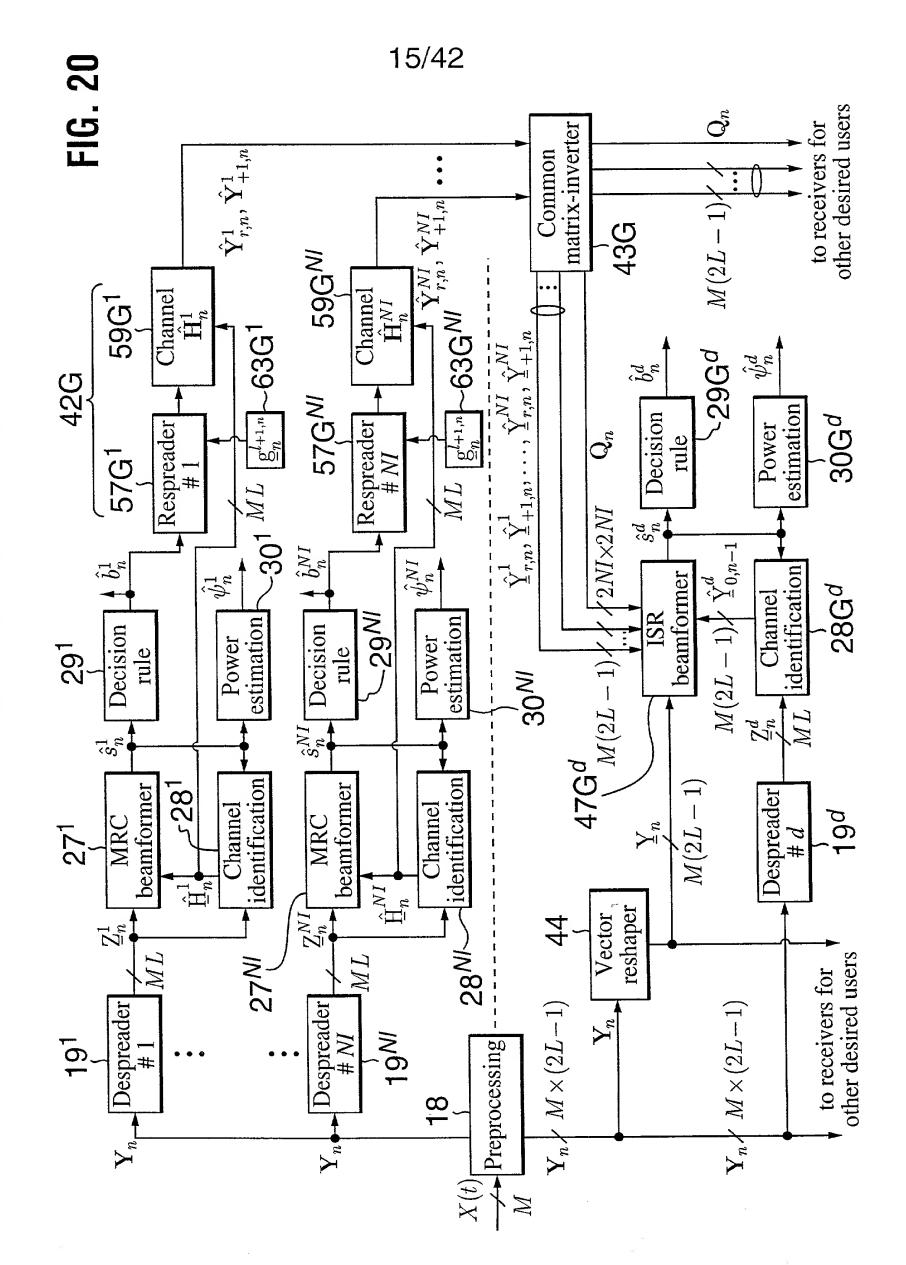


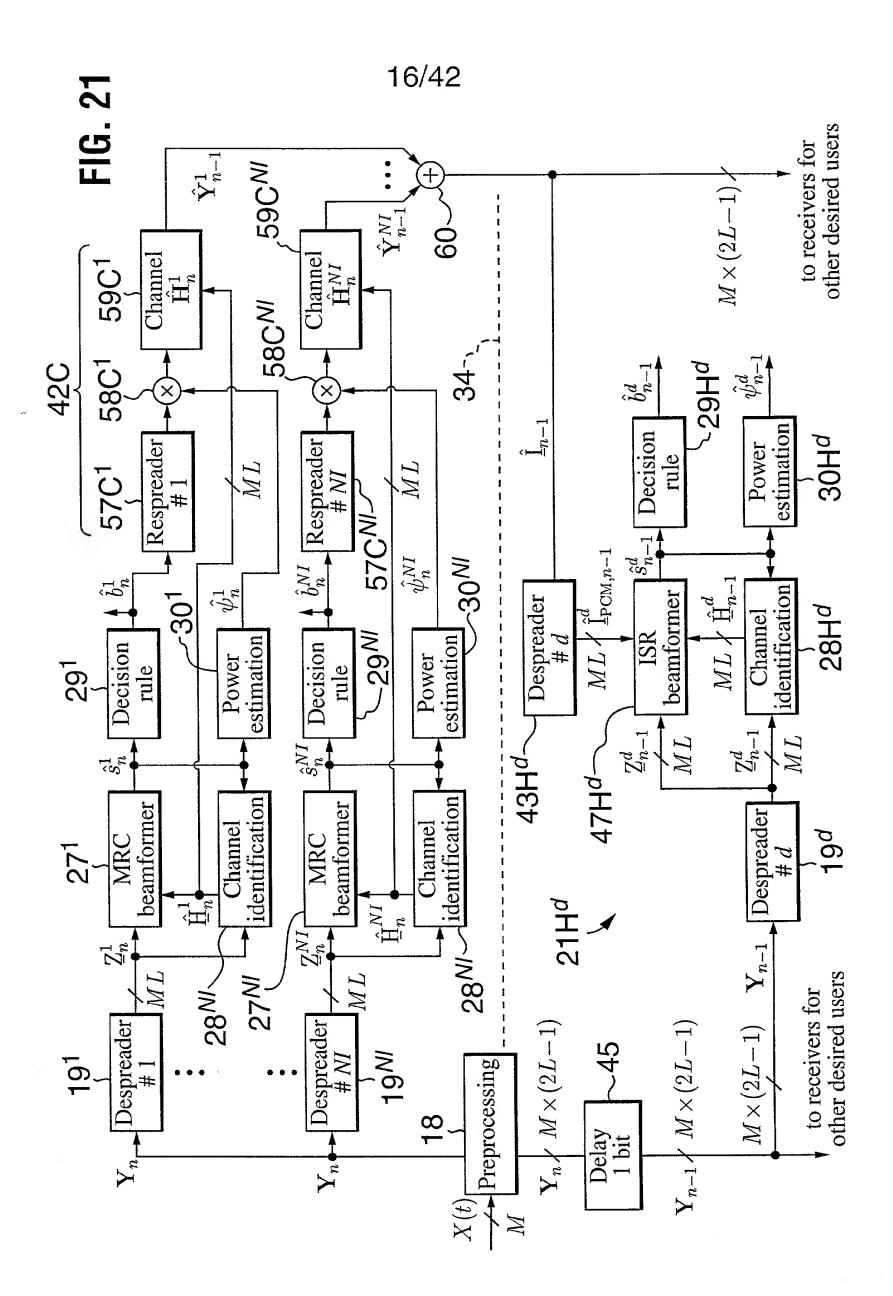


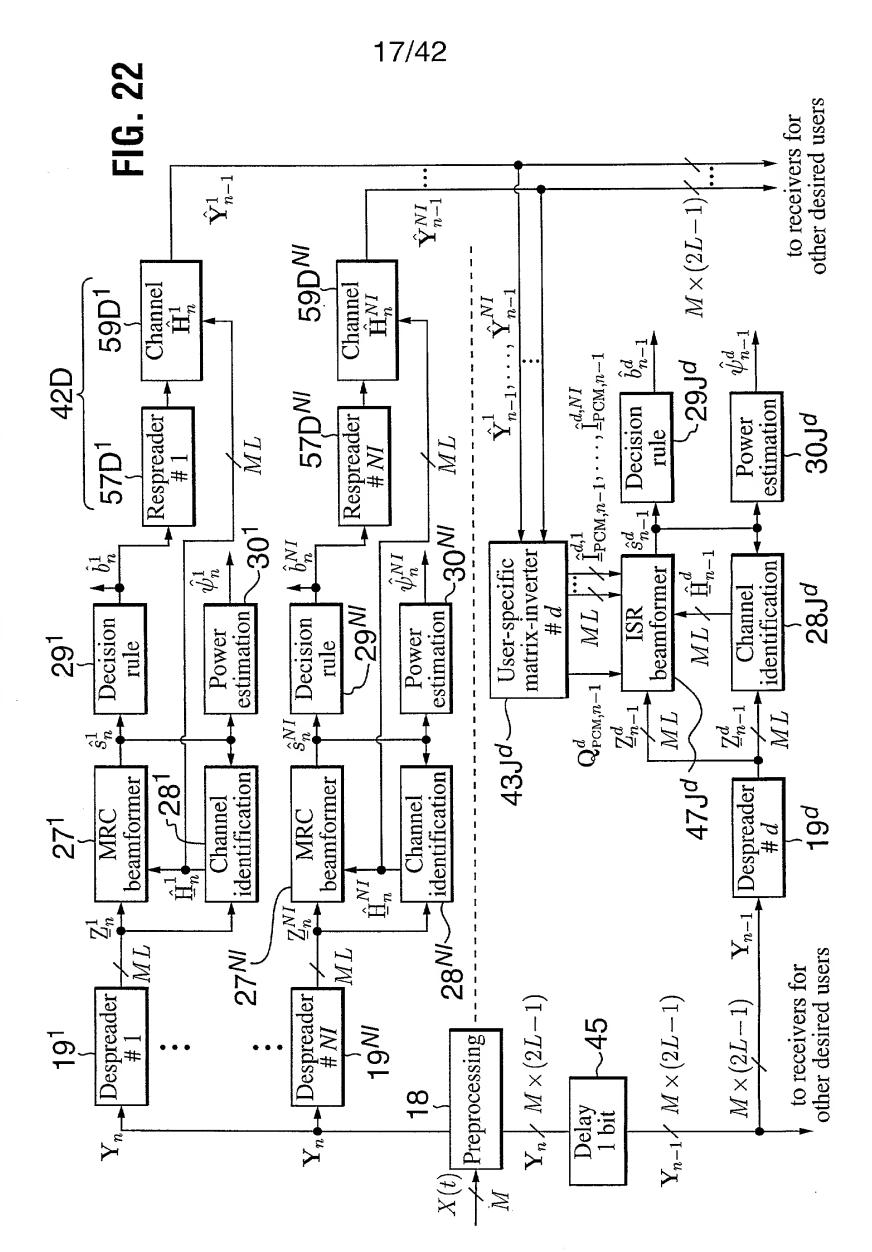


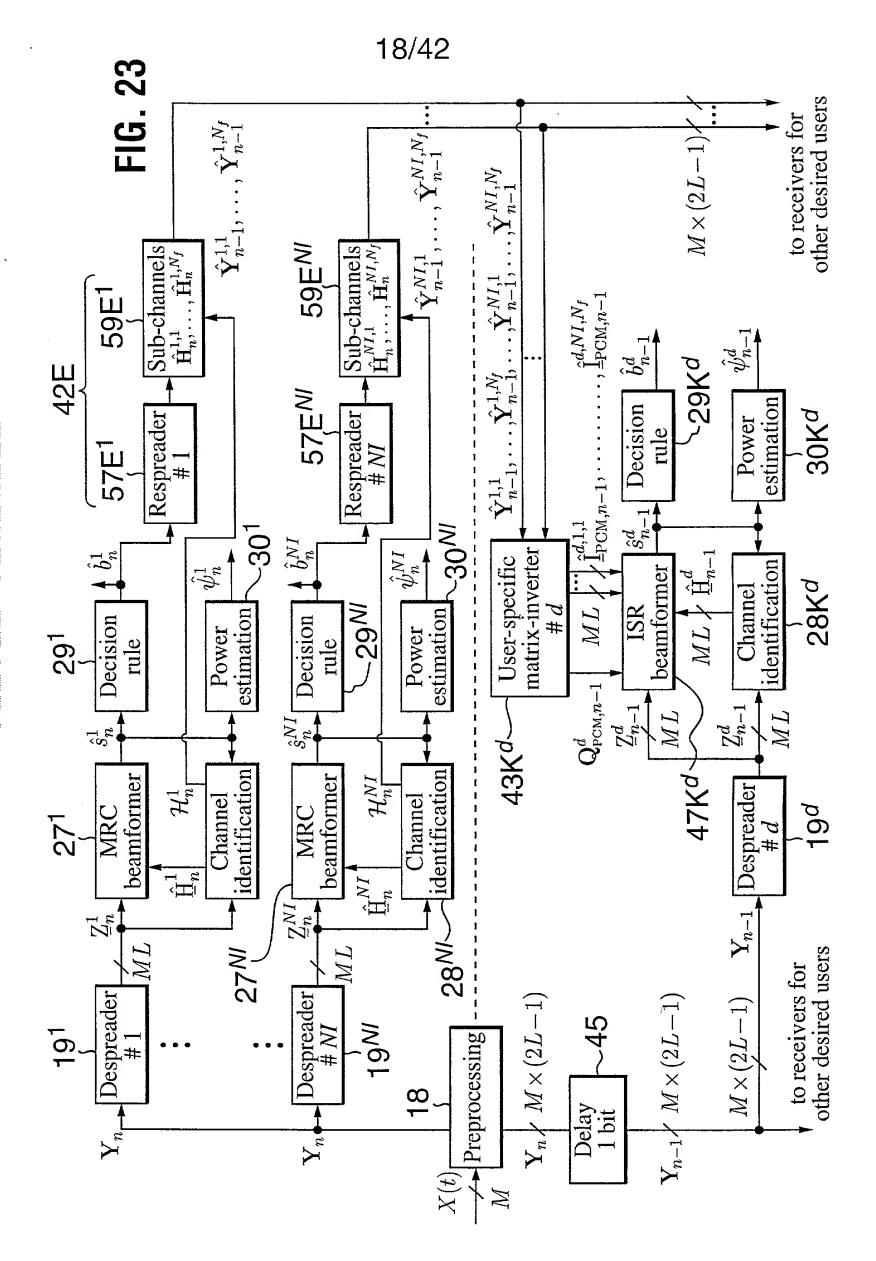


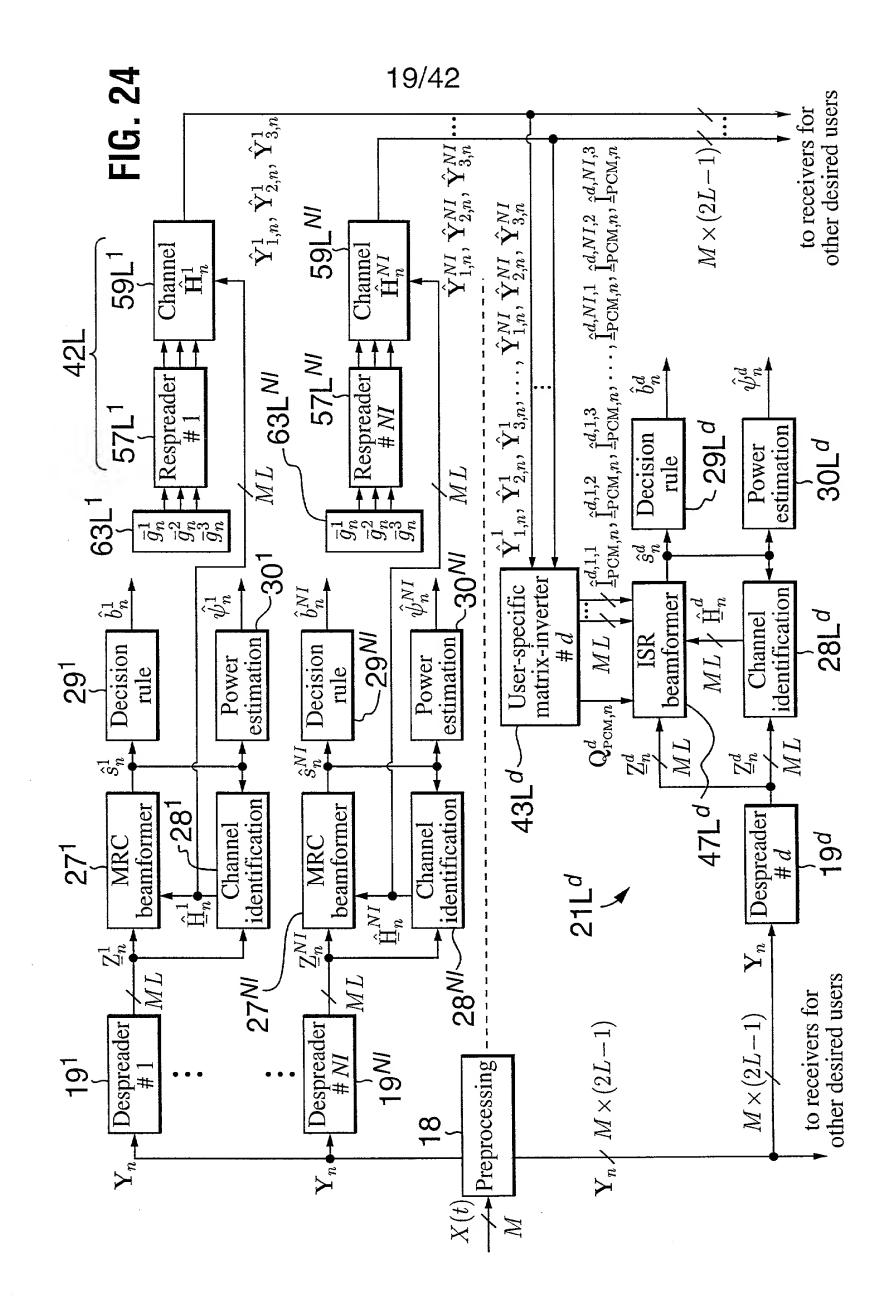
 $g^{1}(t) = \begin{cases} (l_{0,3}; l_{-1,3}; l_{+1,3}) = (3; 2; 1) \\ \vdots \\ g^{2}(t) = \begin{cases} (l_{0,4}; l_{-1,4}; l_{+1,4}) = (1; 3; 2) \\ \end{cases}$ flg. 19

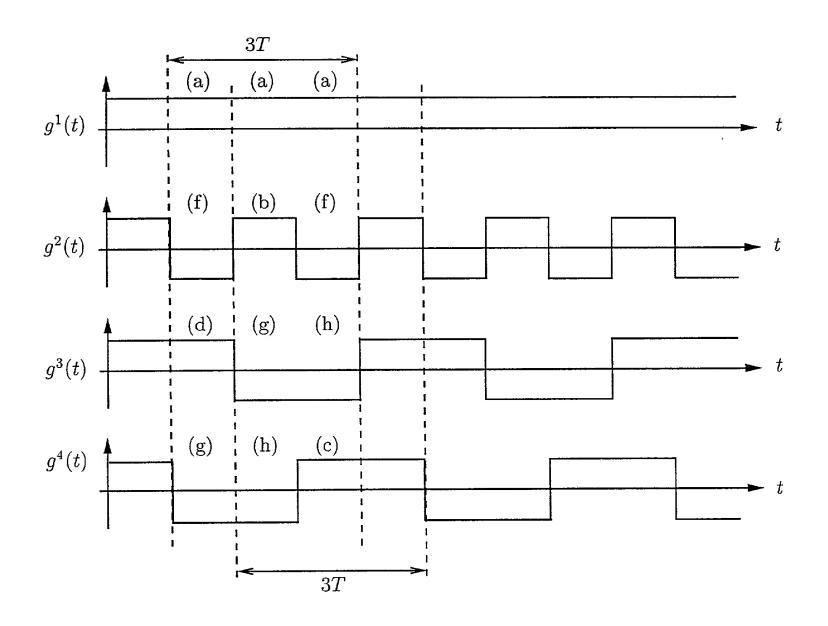






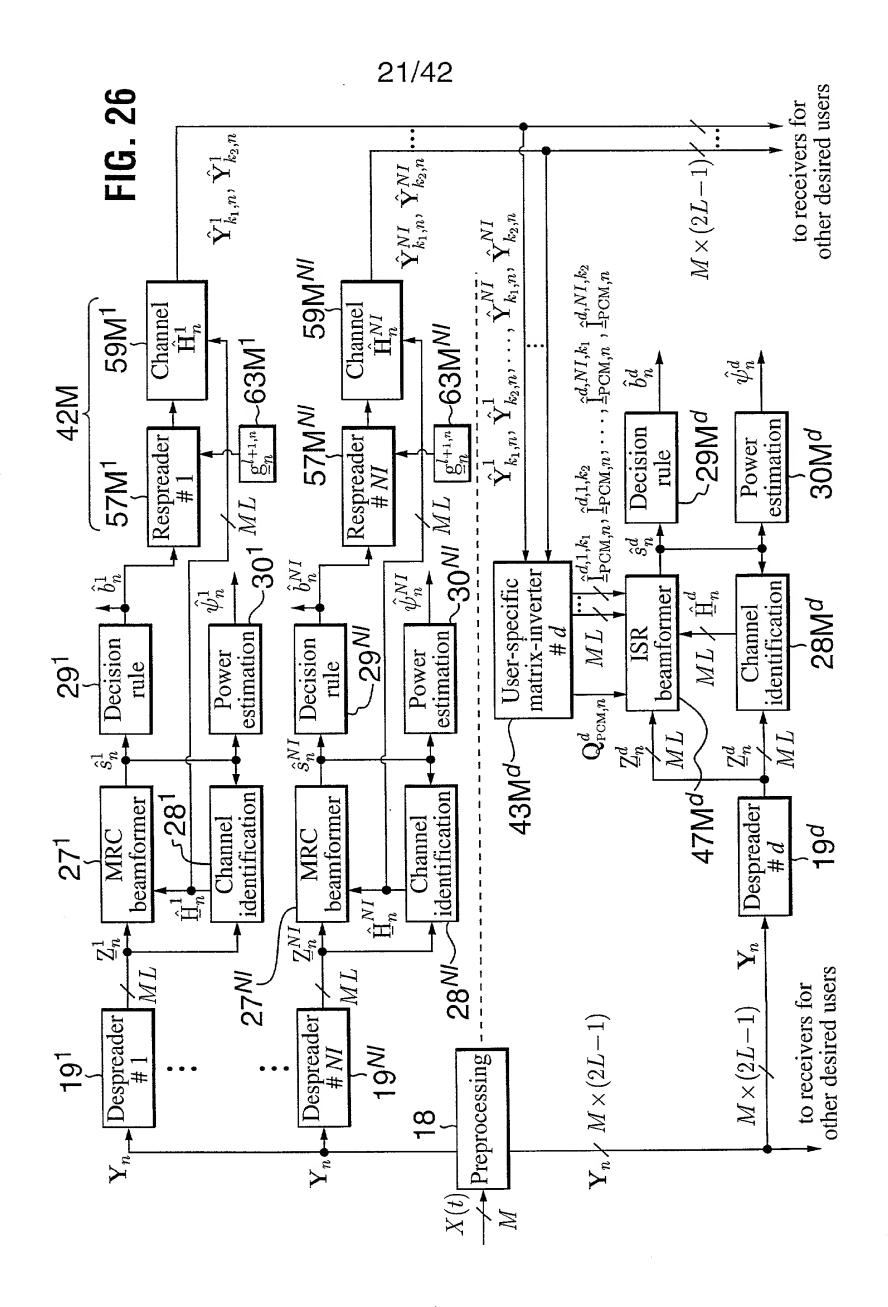






The state of the s

FIG. 25



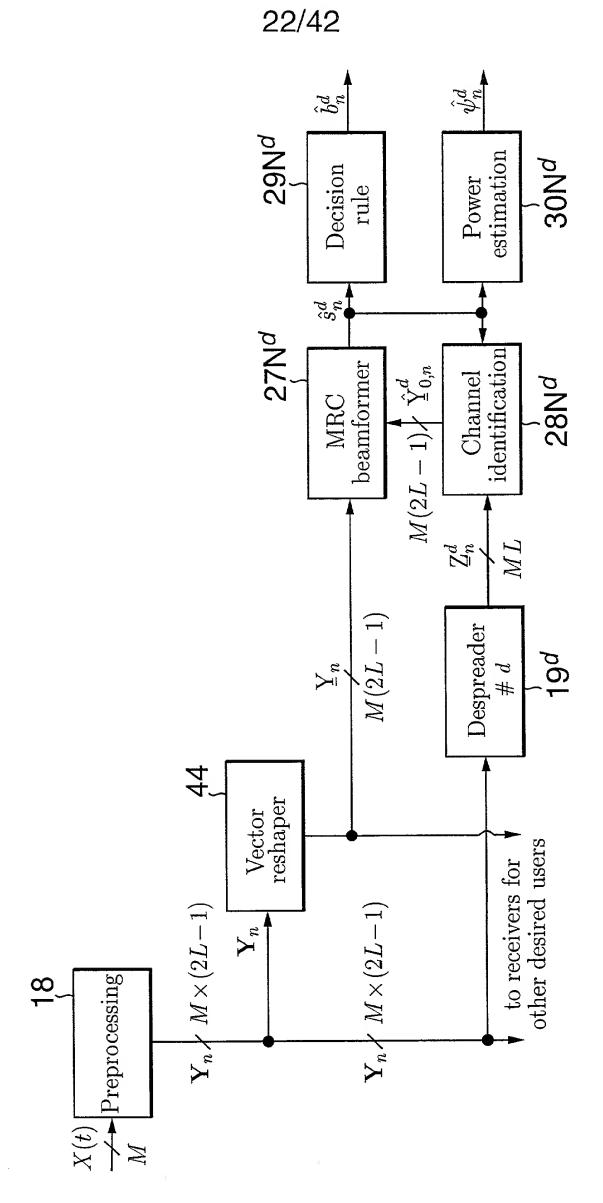
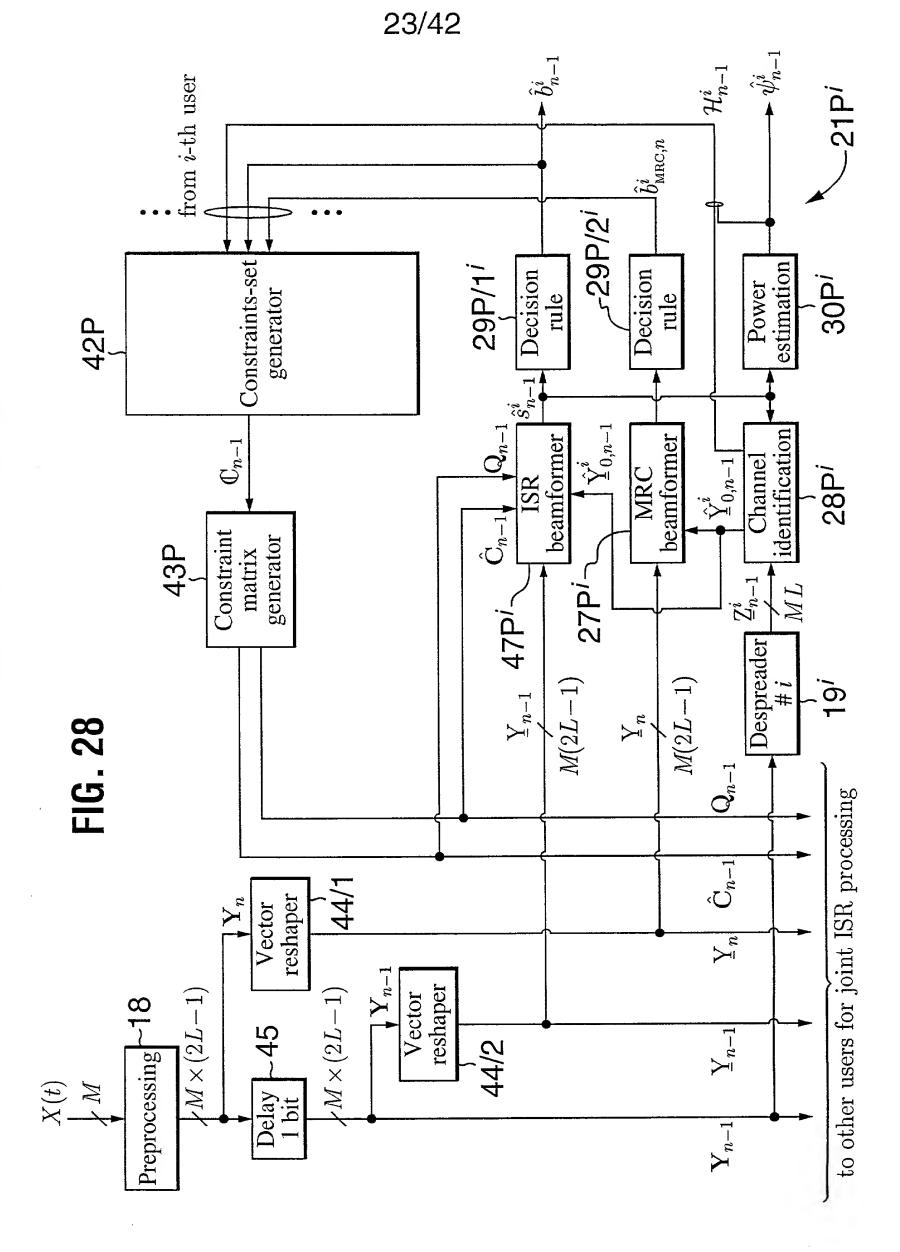


FIG. 27



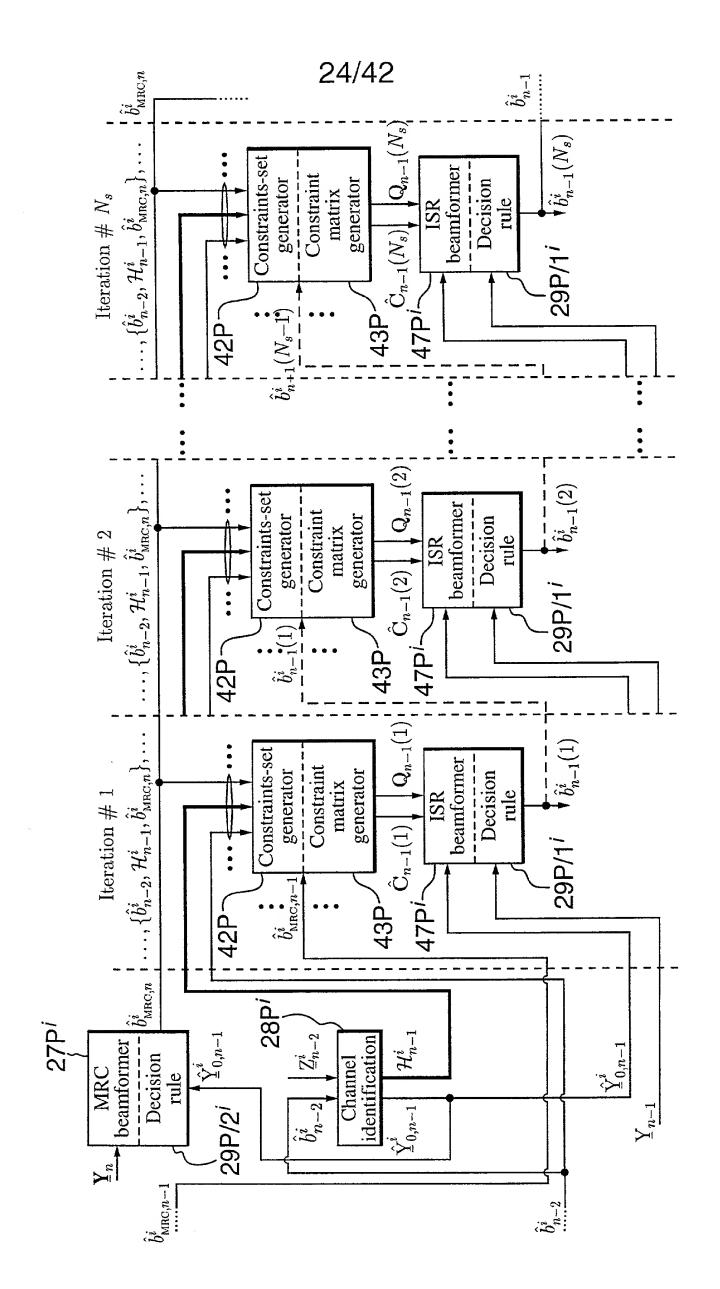


FIG. 29

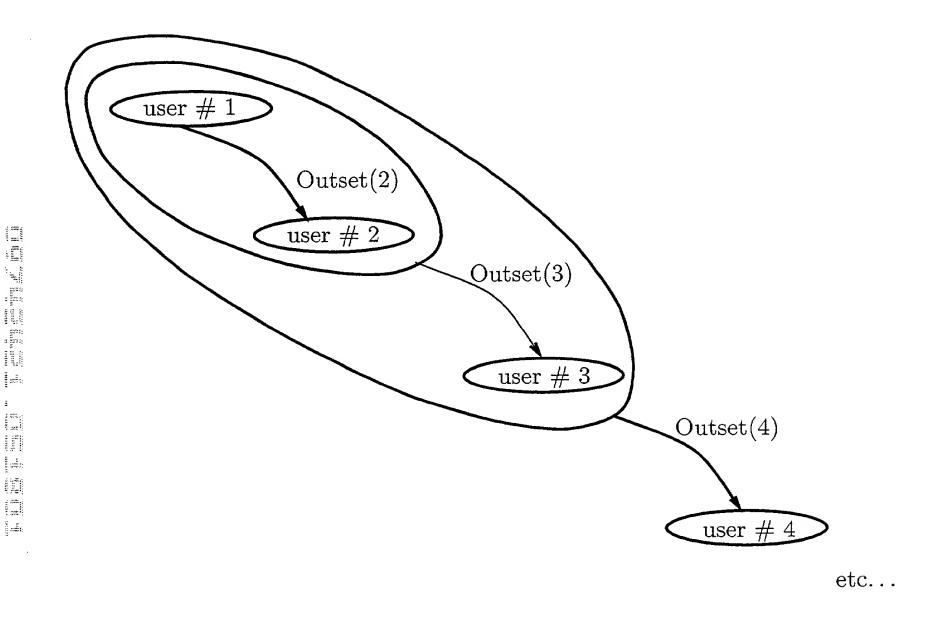


FIG. 30

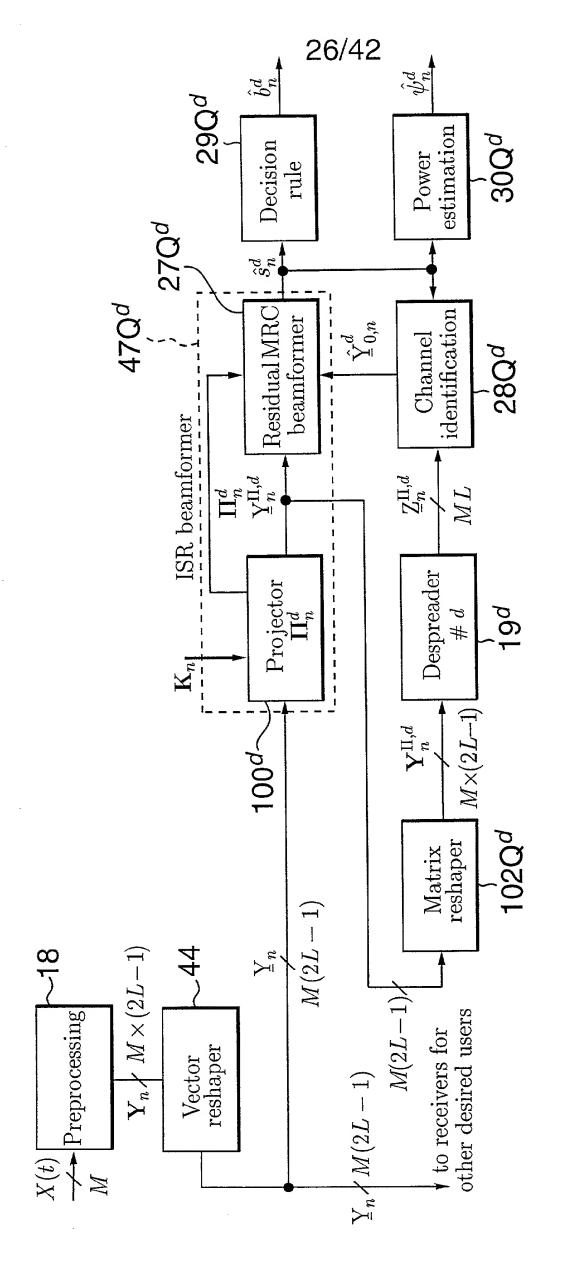
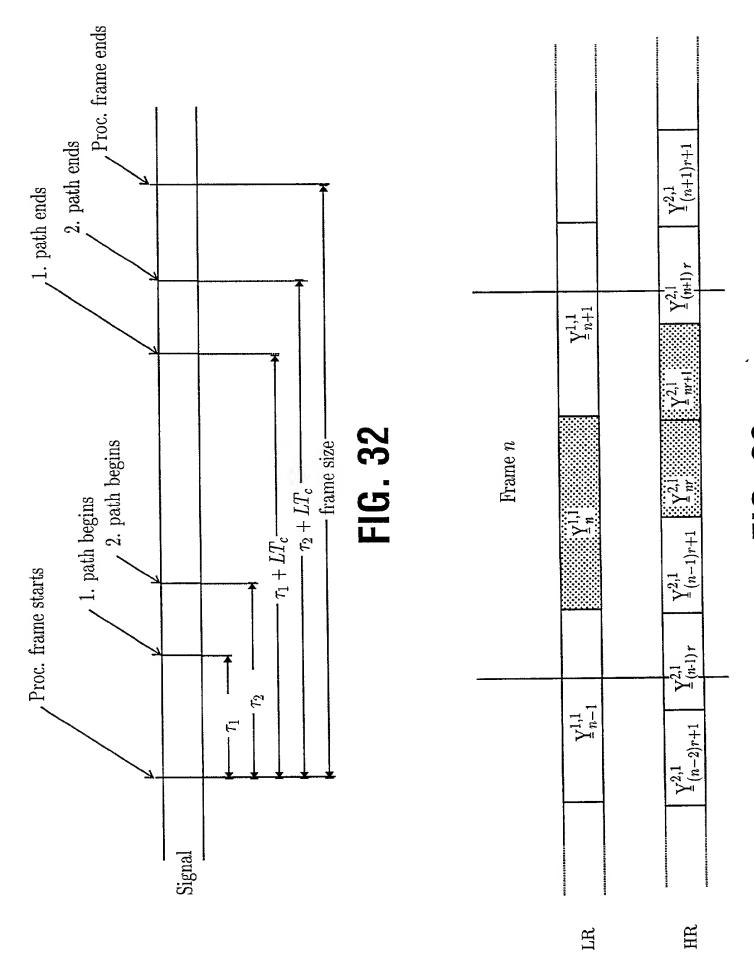


FIG. 31



The state of the state and state the state is the state and state

FIG. 33

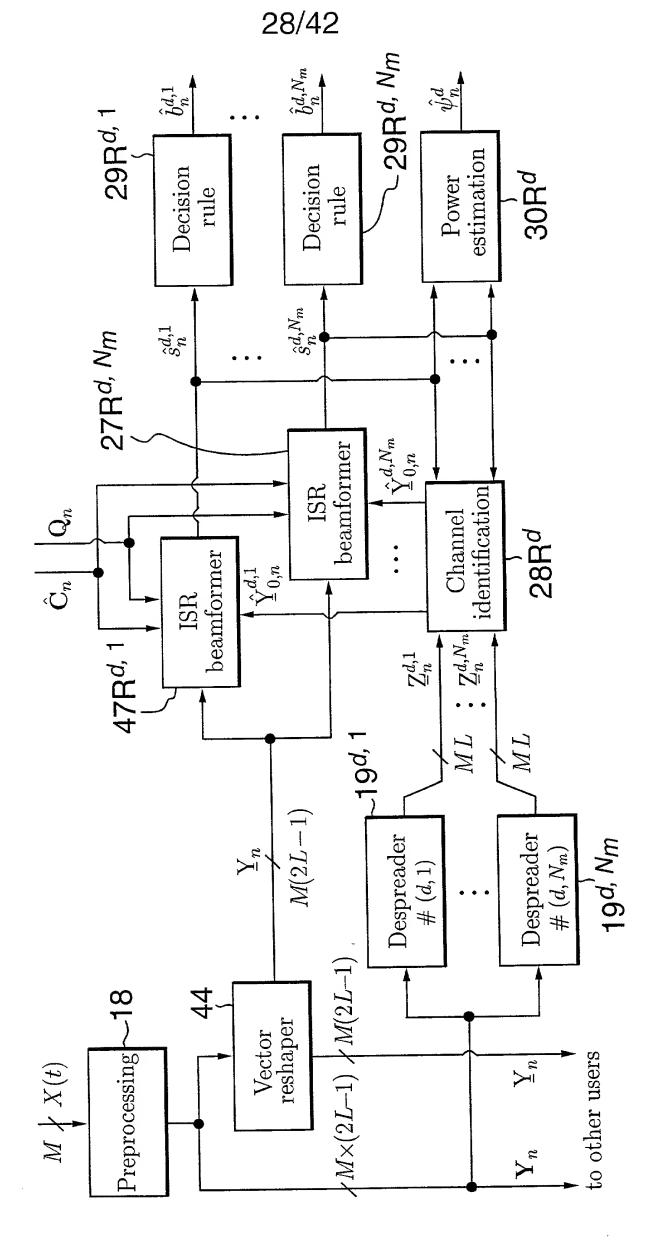


FIG. 34

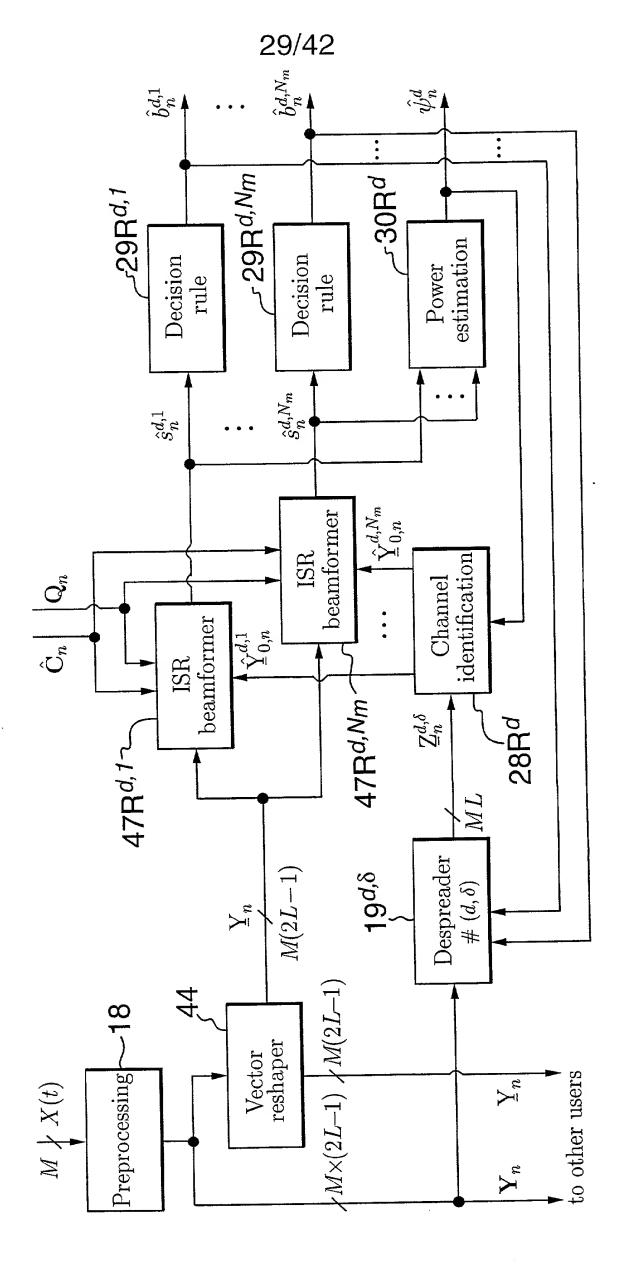


FIG. 35

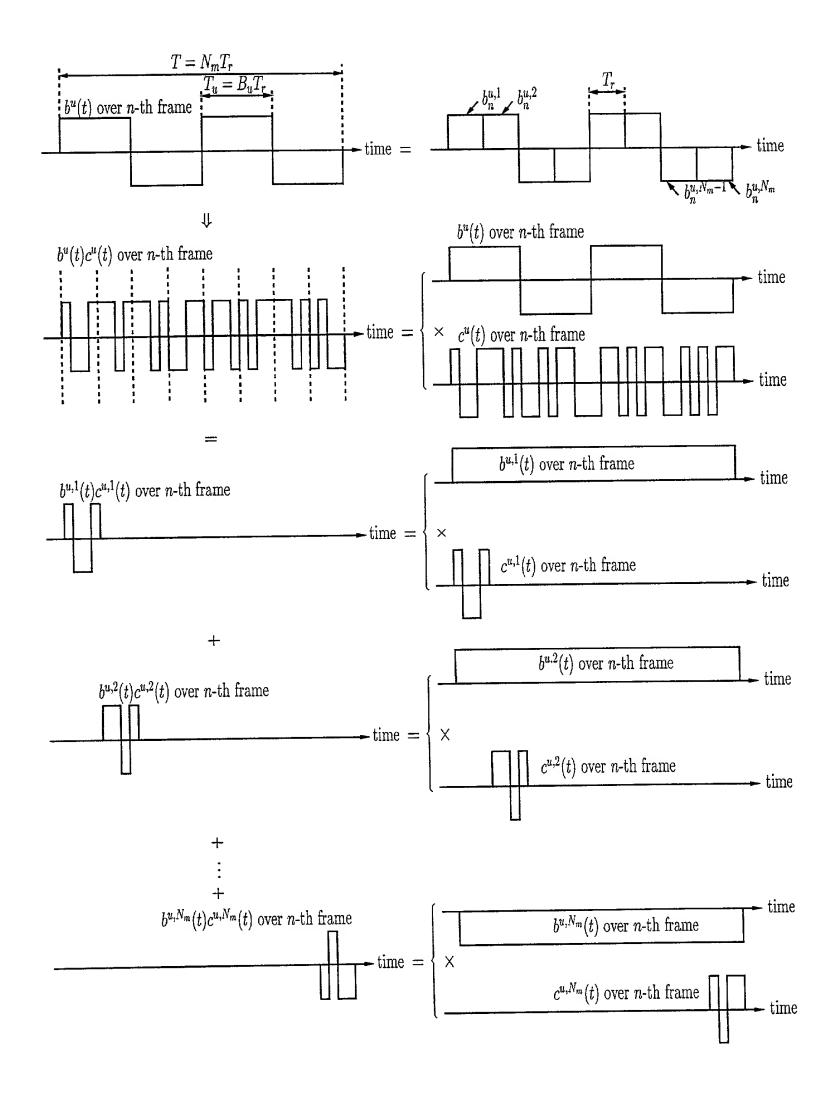


FIG. 36

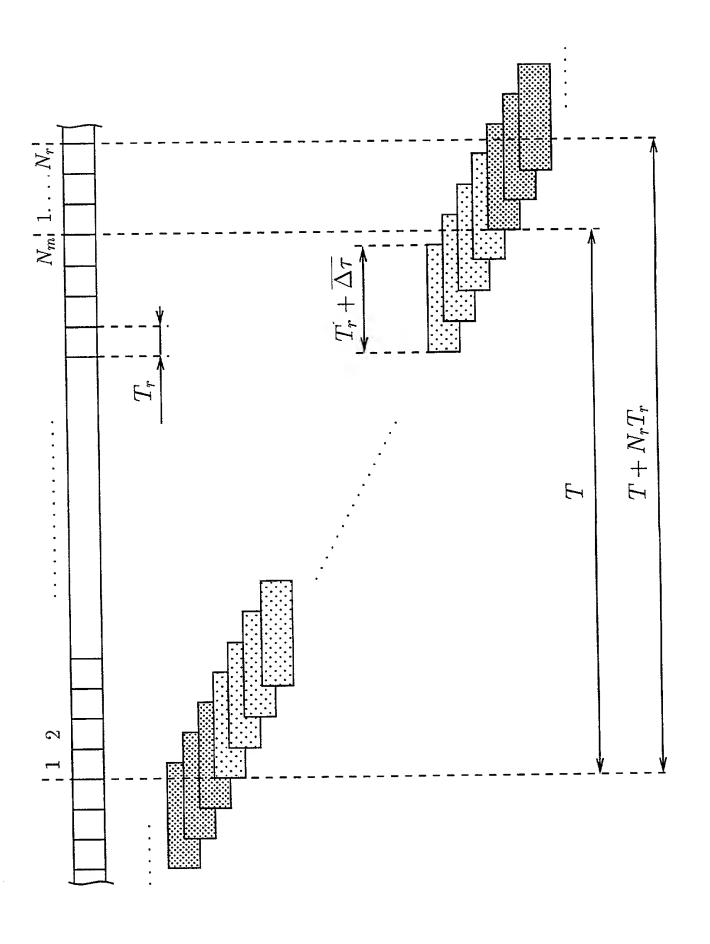


FIG. 37

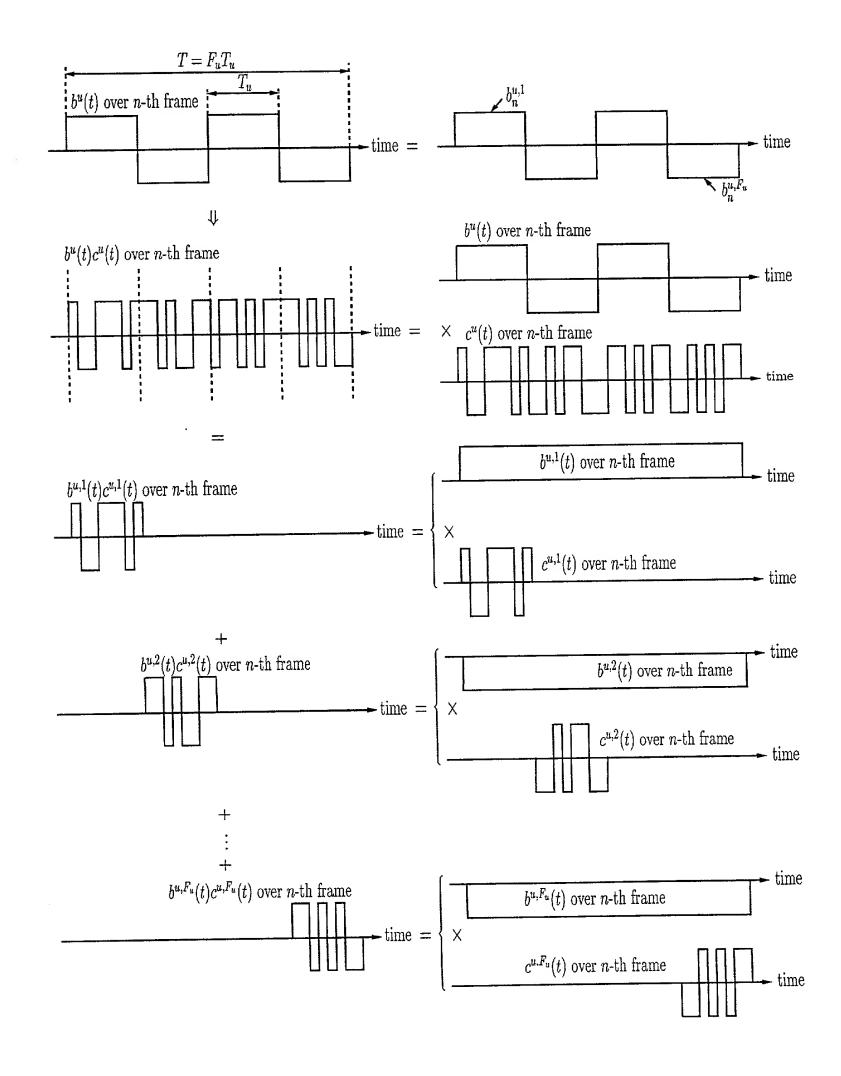
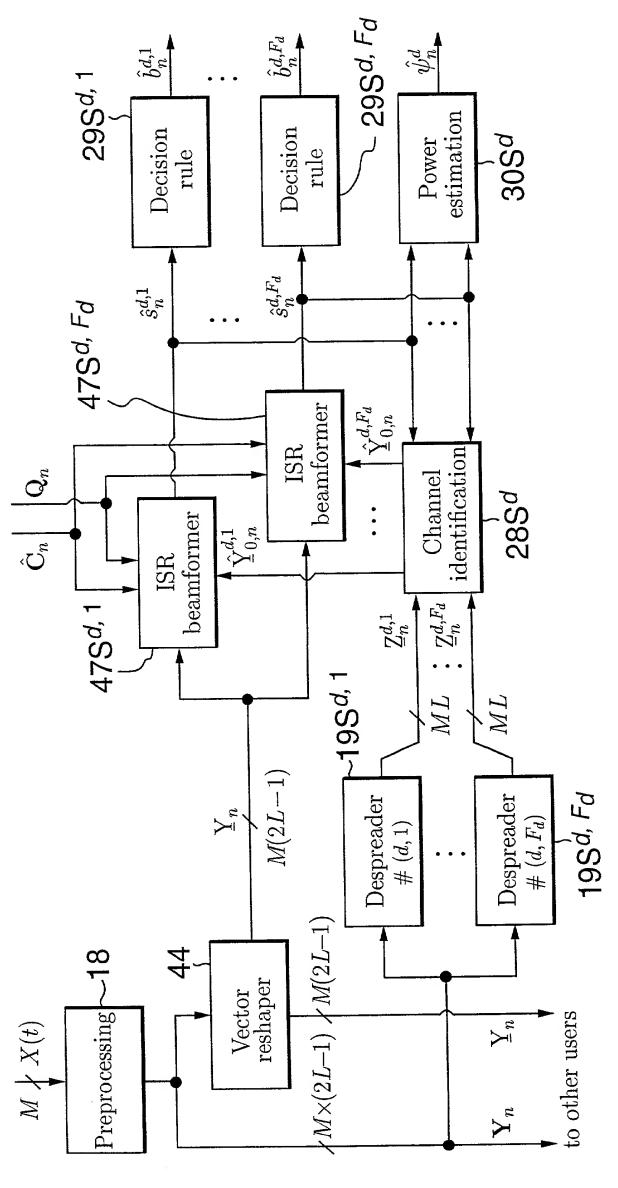


FIG. 38



33/42

FIG. 39

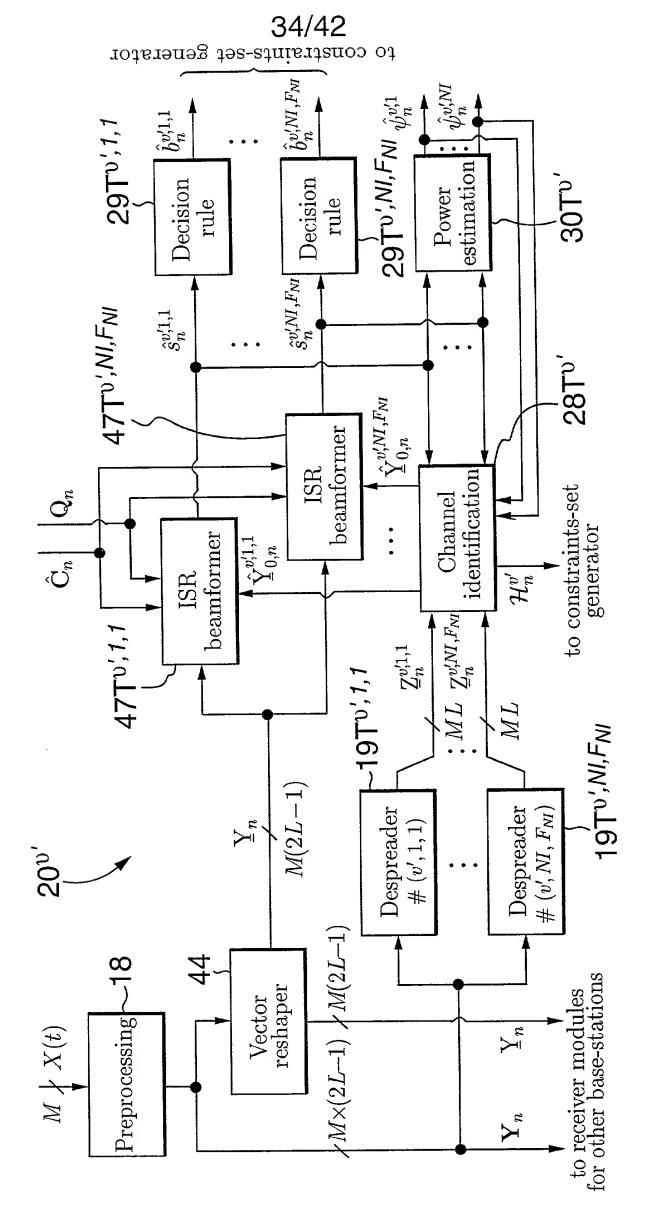


FIG. 40

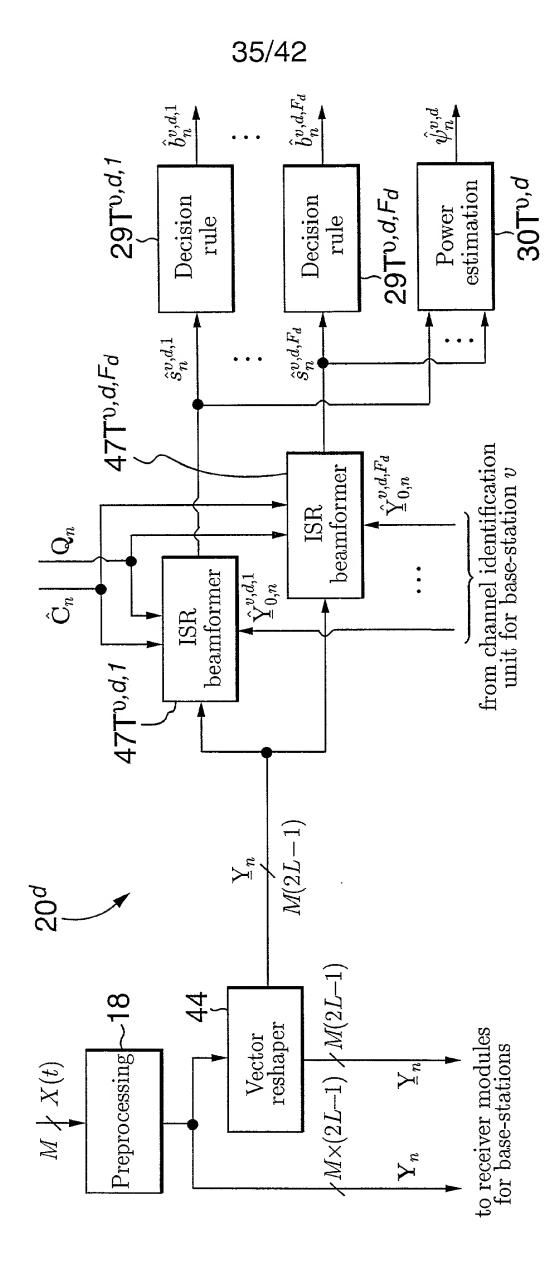


FIG. 41

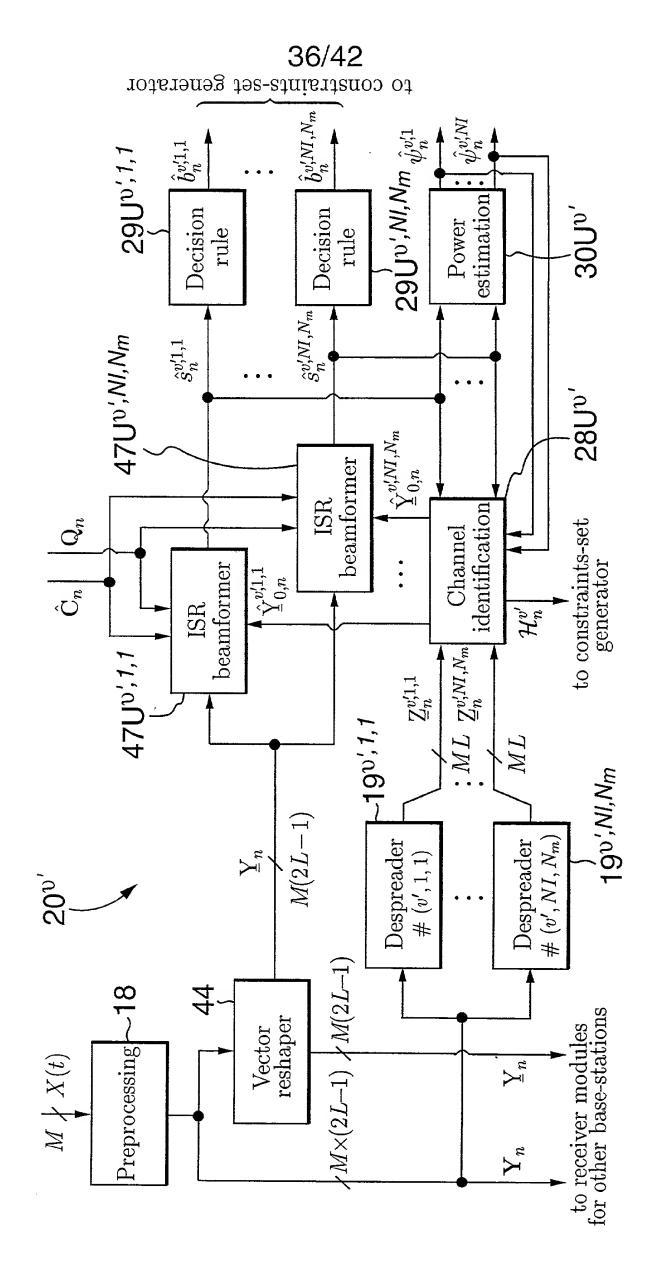


FIG. 42

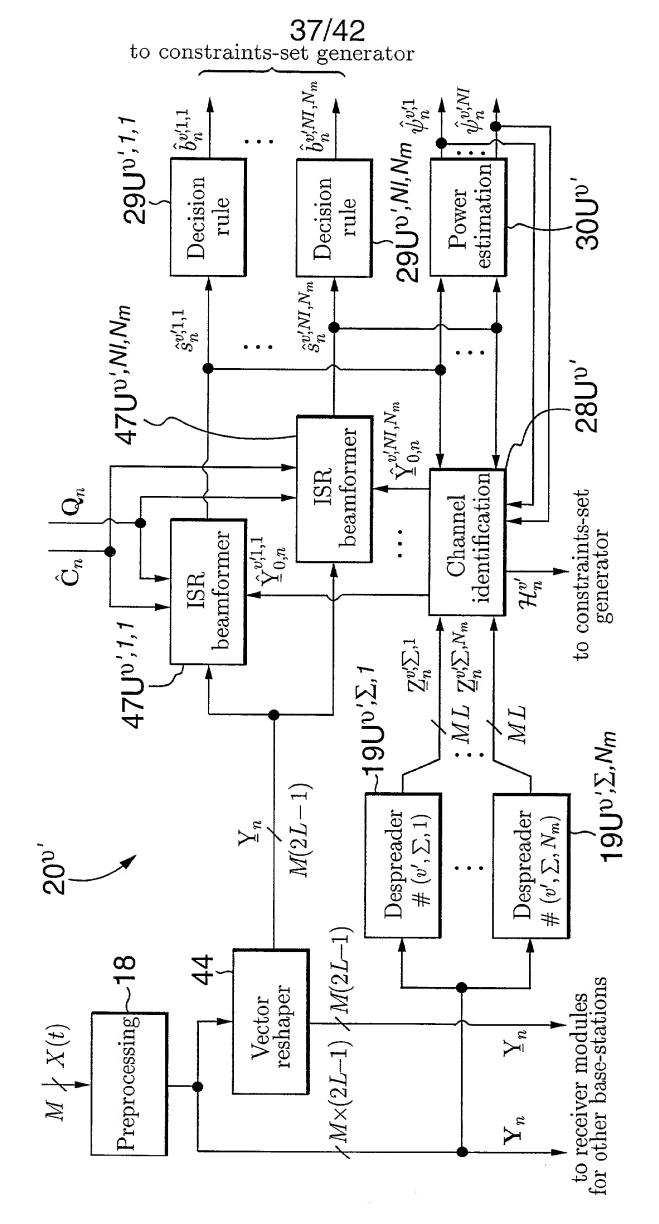
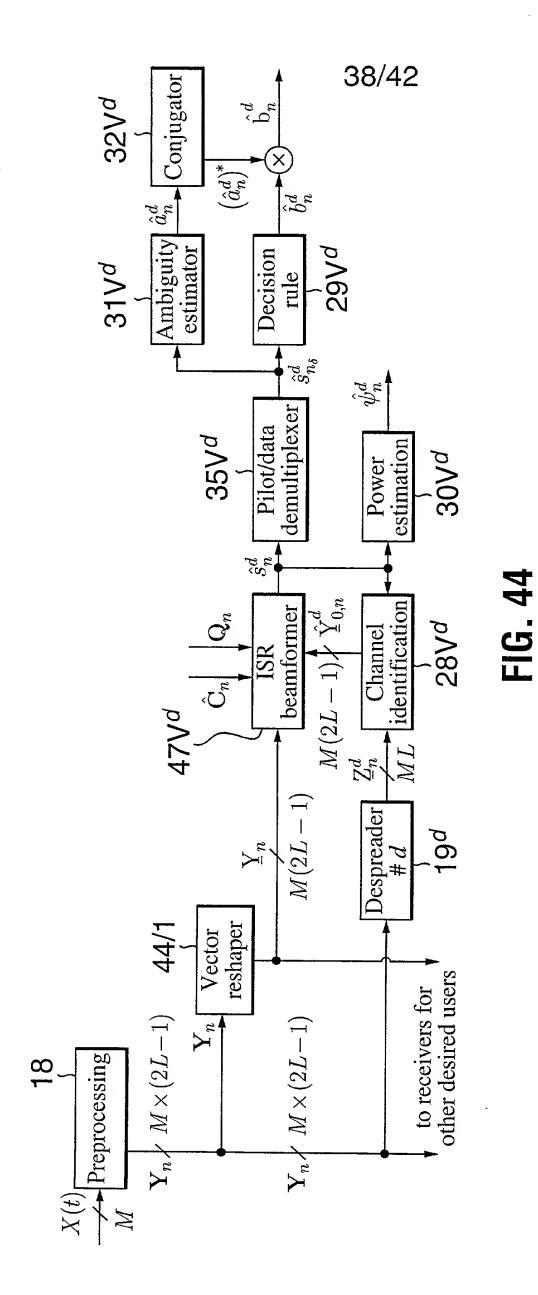


FIG. 43



 \hat{a}_n^d Decision rule or averaging Smoothing Buffer $\hat{s}_n^{\pi,d}$ or $\hat{s}_{n_\pi}^d$

FIG. 45

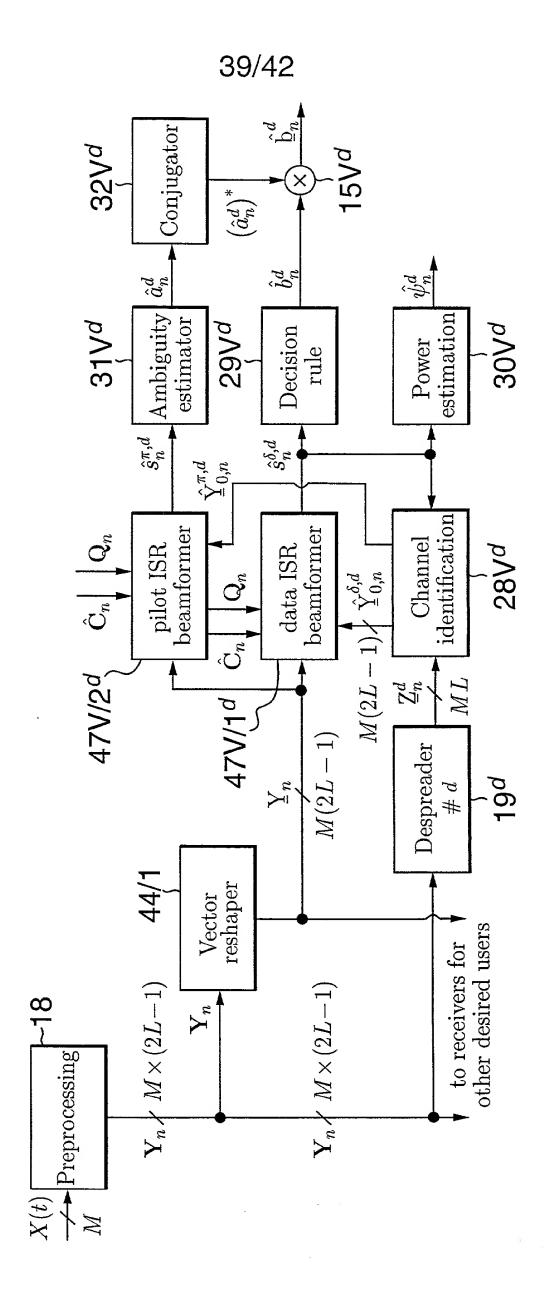
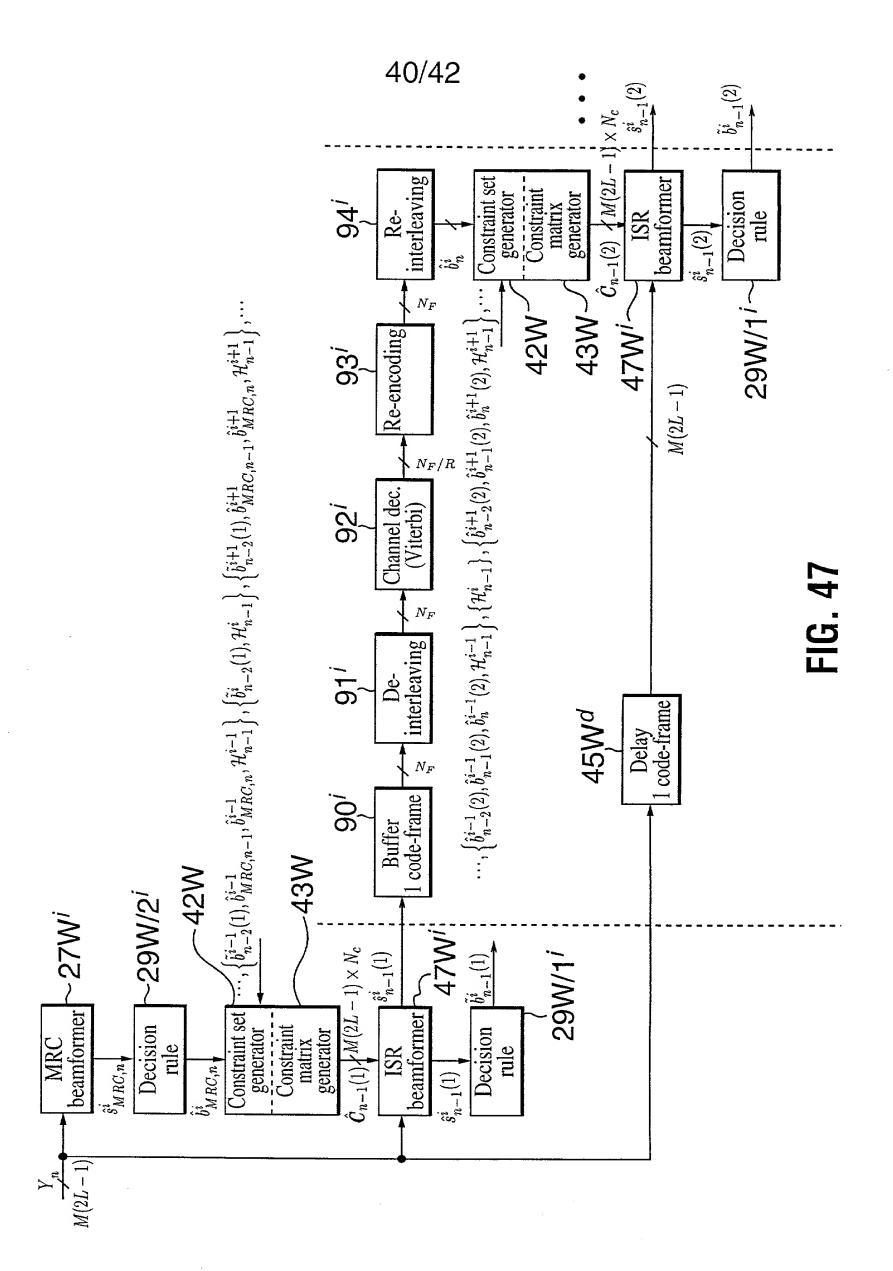
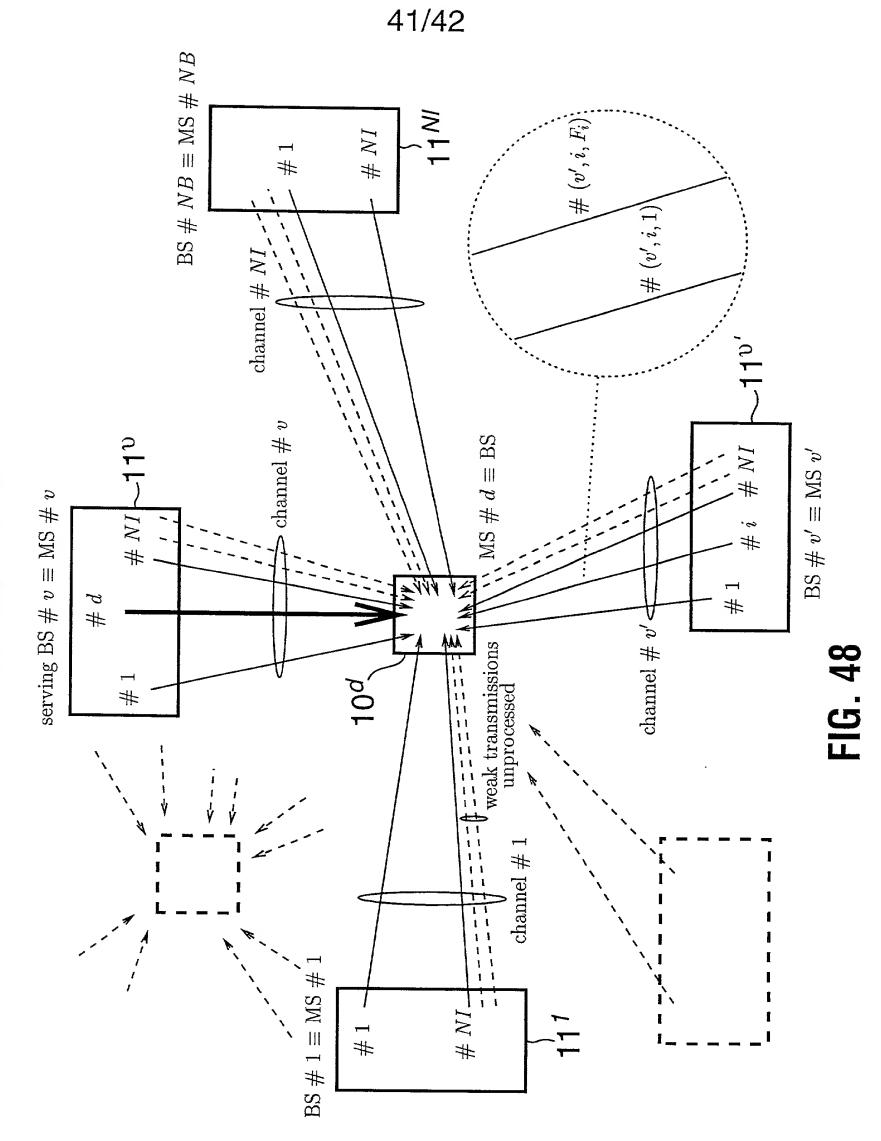


FIG. 46





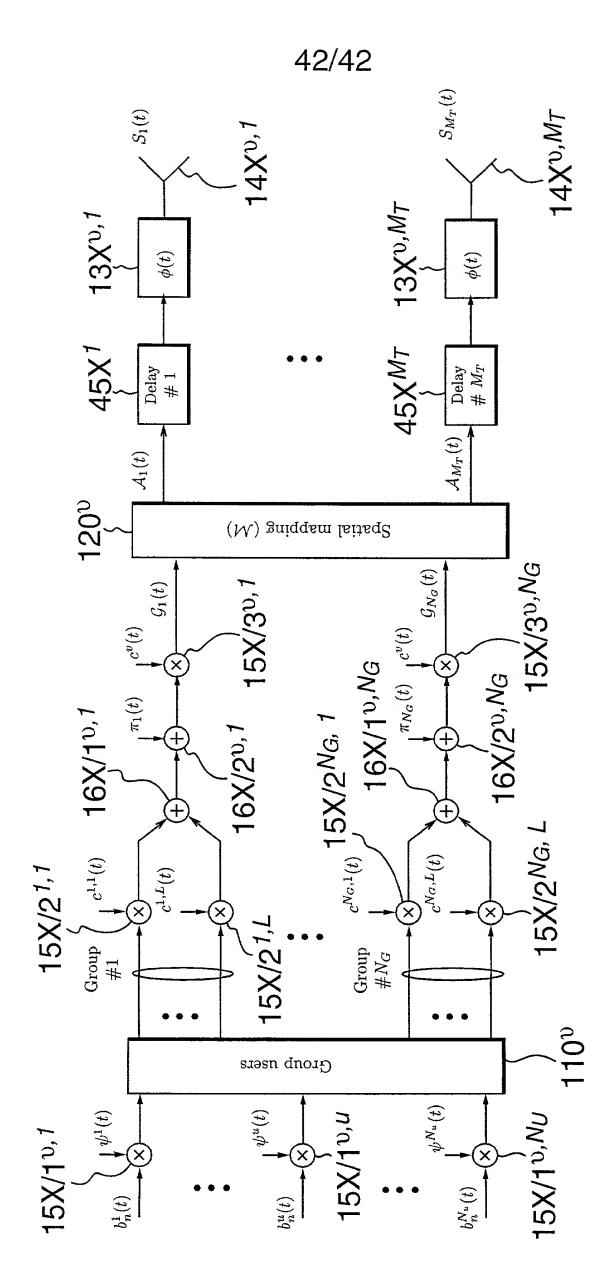


FIG. 49